

(12) **United States Patent**  
**Fenny**

(10) **Patent No.:** **US 9,061,760 B2**  
(45) **Date of Patent:** **Jun. 23, 2015**

(54) **INDEPENDENT BLADE CONTROL SYSTEM  
WITH ROTARY BLADE ACTUATOR**

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(73) Assignee: **Bell Helicopter Textron Inc.**, Fort  
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(\*) Notice: Subject to any disclaimer, the term of this  
patent is extended or adjusted under 35  
U.S.C. 154(b) by 416 days.

(21) Appl. No.: **13/565,577**

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(65) **Prior Publication Data**

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(51) **Int. Cl.**  
**B64C 27/52** (2006.01)  
**B64C 27/72** (2006.01)  
**F04C 9/00** (2006.01)  
**F15B 15/12** (2006.01)

(52) **U.S. Cl.**  
CPC ..... **B64C 27/72** (2013.01); **B64C 2027/7216**  
(2013.01); **F04C 9/002** (2013.01); **F15B 15/12**  
(2013.01); **Y02T 50/34** (2013.01)

(58) **Field of Classification Search**  
USPC ..... 244/17.25, 17.27, 99.2, 99.5, 99.6,  
244/99.7, 17.11; 92/121, 122, 123, 124,  
92/125; 416/157 A, 158  
See application file for complete search history.

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*Primary Examiner* — Benjamin P Lee

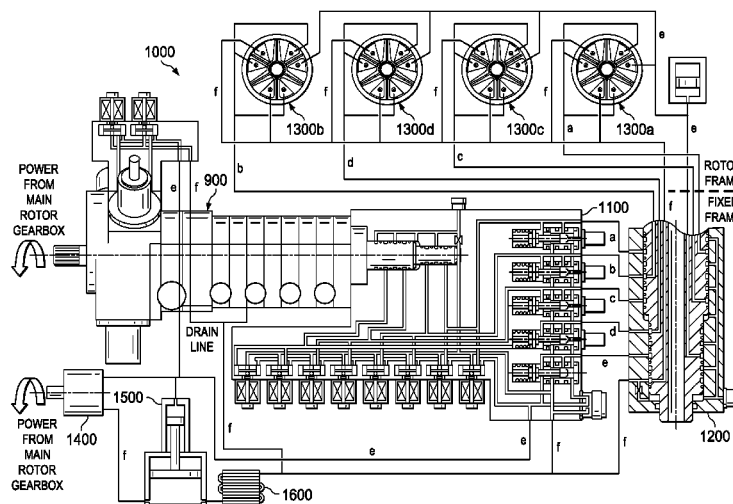
*Assistant Examiner* — Alexander V Giczy

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Inc.; Christopher S. Storm

(57) **ABSTRACT**

According to one embodiment, a rotary blade actuator includes a housing, a vane disposed within the housing, a shaft disposed at least partially within the housing and coupled to the vane. The vane comprises a first vane surface disposed within a first chamber between a first fluid opening and a second fluid opening and a second vane surface disposed within a second chamber between a third fluid opening and a fourth fluid opening. The first and third fluid openings are configured to provide a first fluid to the first chamber and the second chamber at a first pressure, the second fluid opening is configured to provide a second fluid to the first chamber at a second pressure, and the fourth fluid opening is configured to provide a third fluid to the second chamber at a third pressure different from the second pressure.

**19 Claims, 56 Drawing Sheets**



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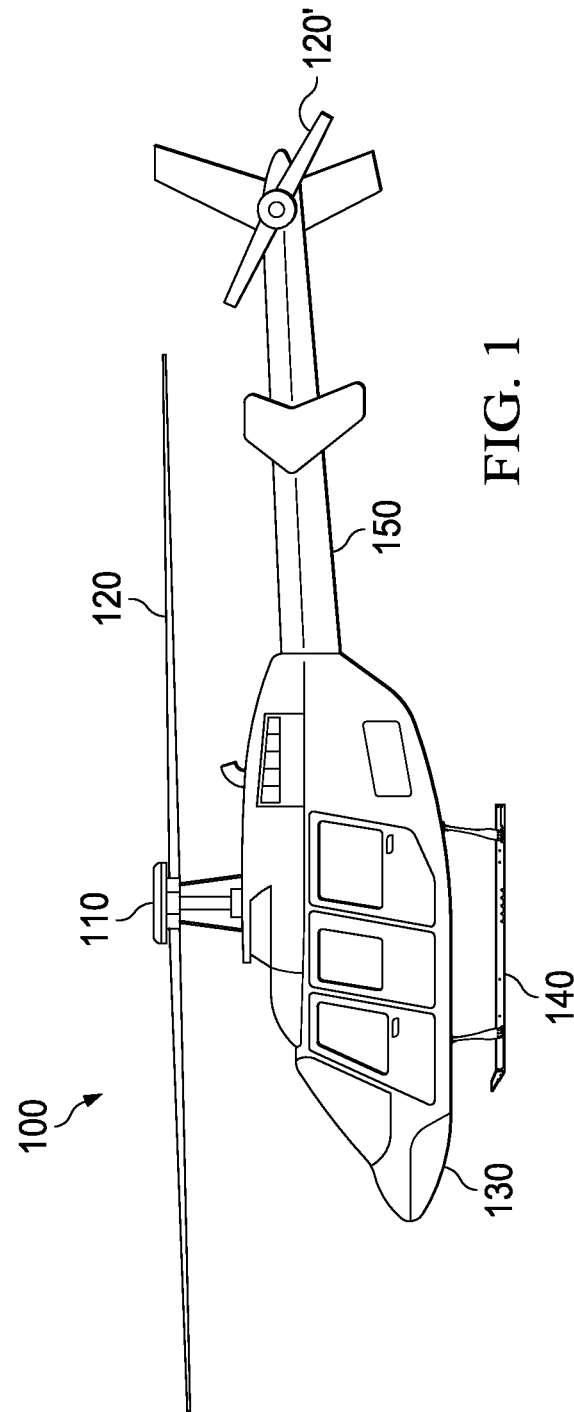
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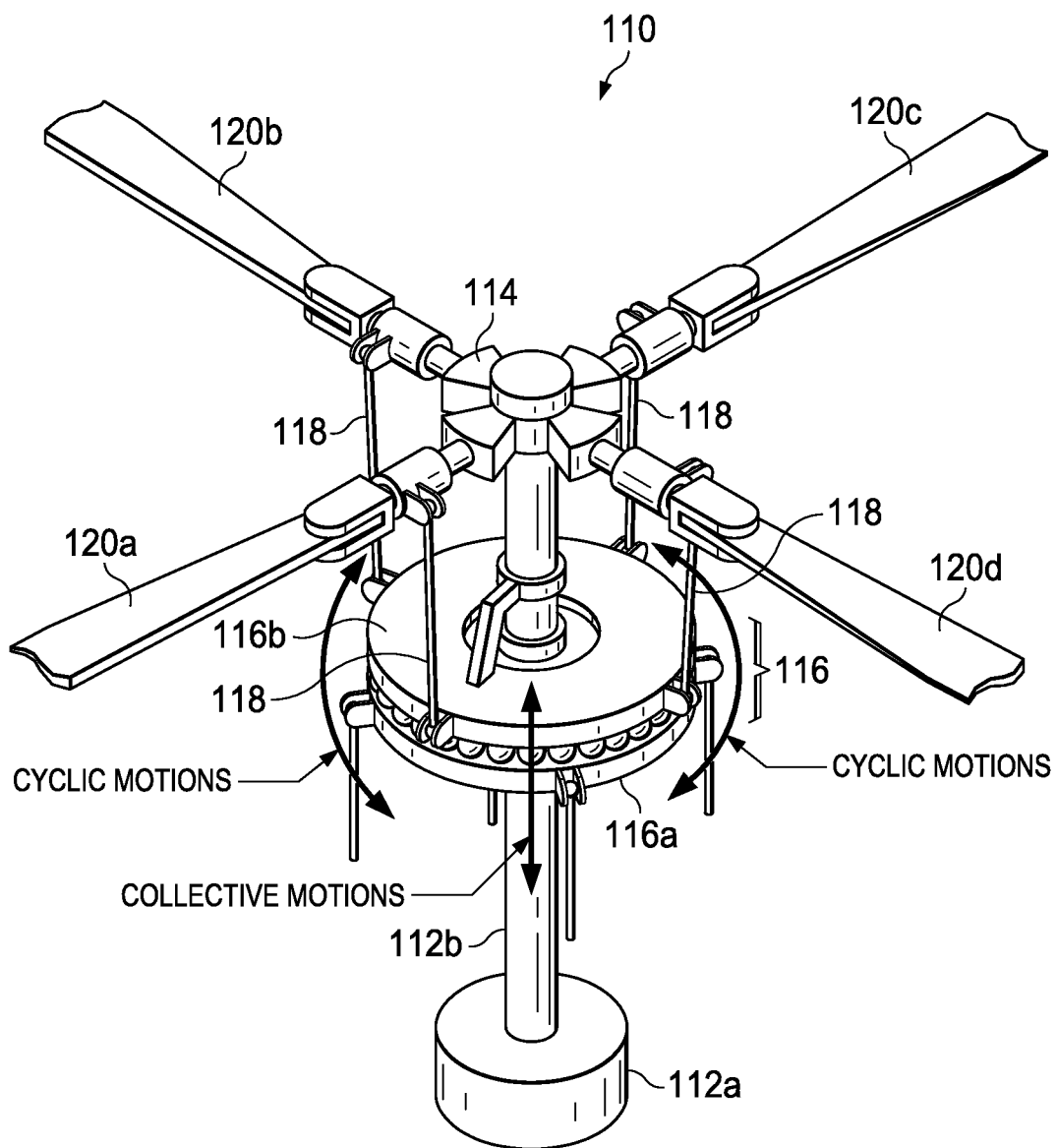
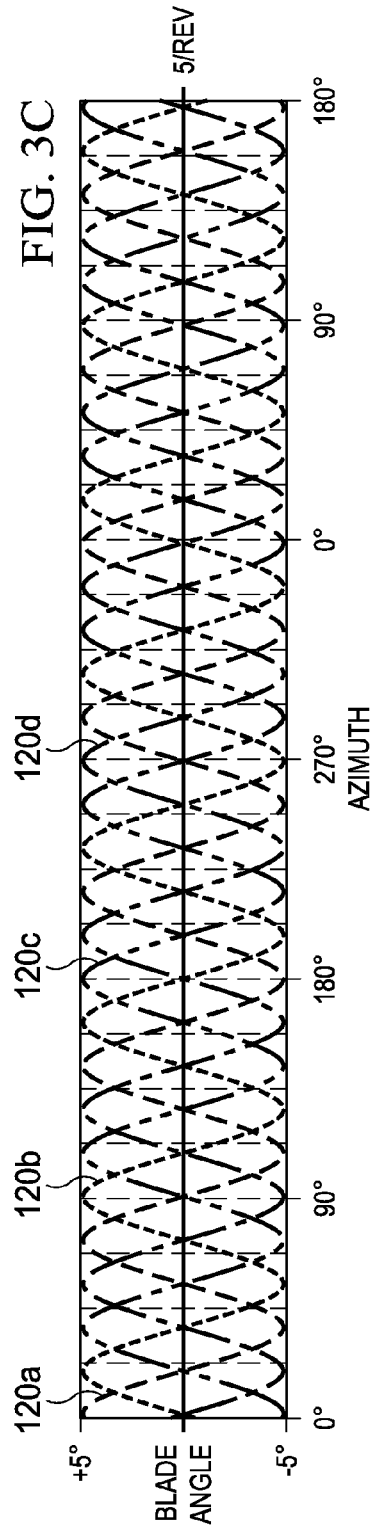
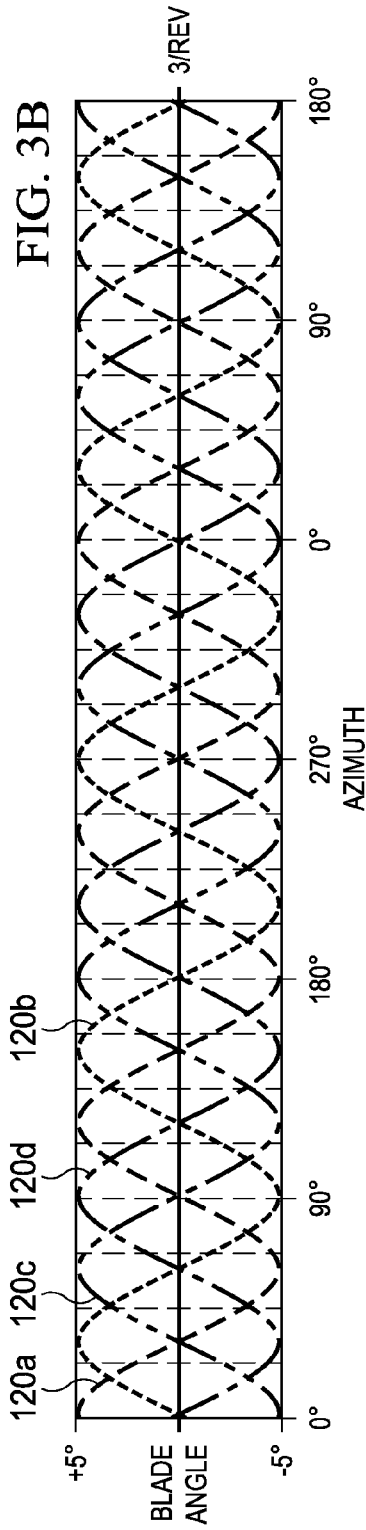
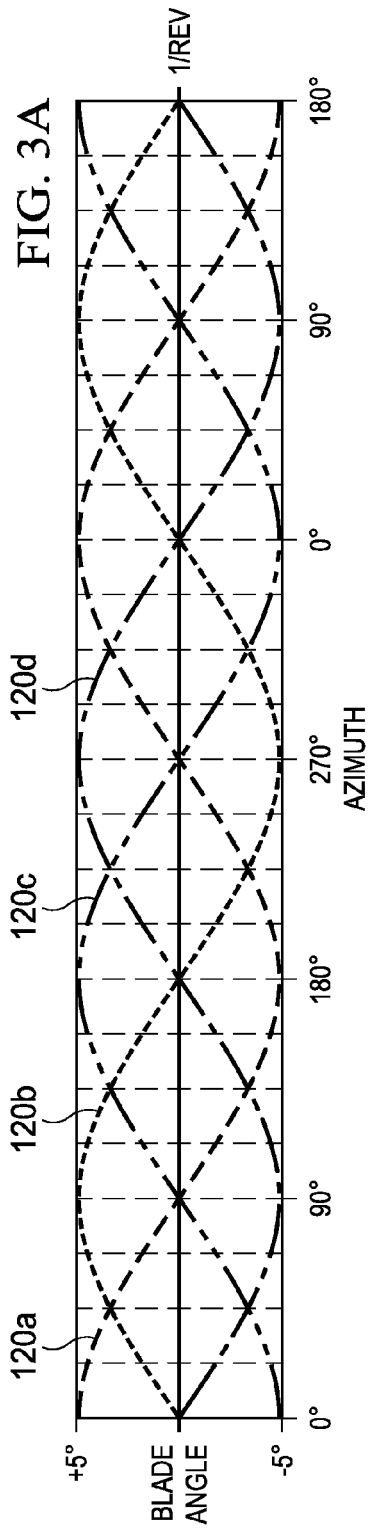
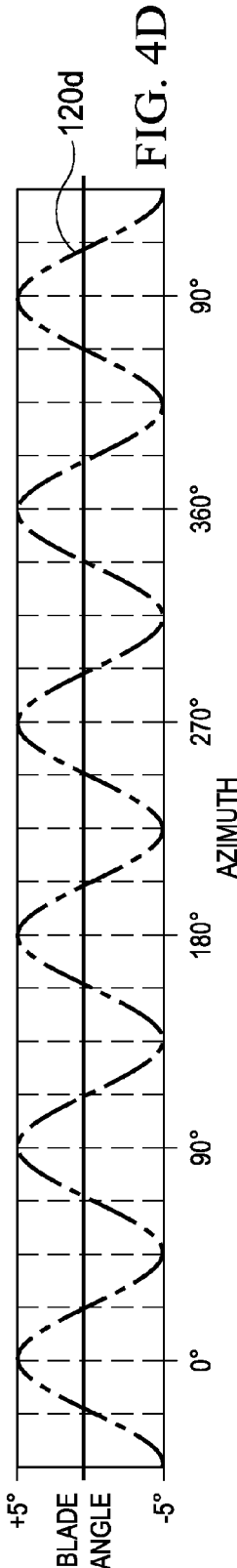
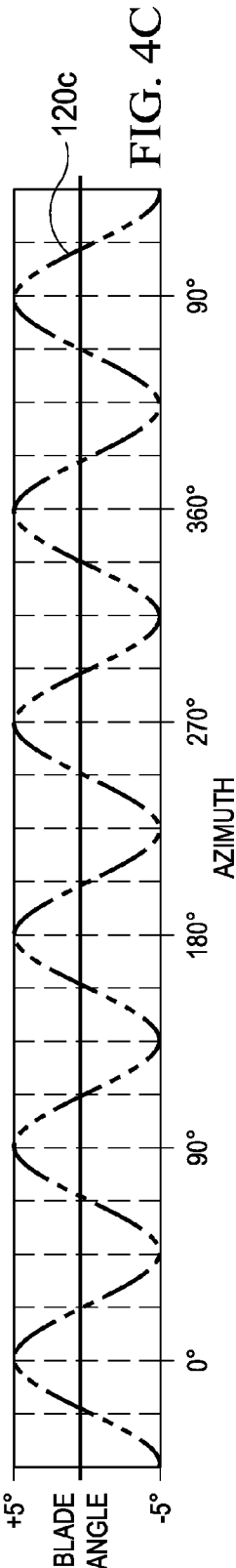
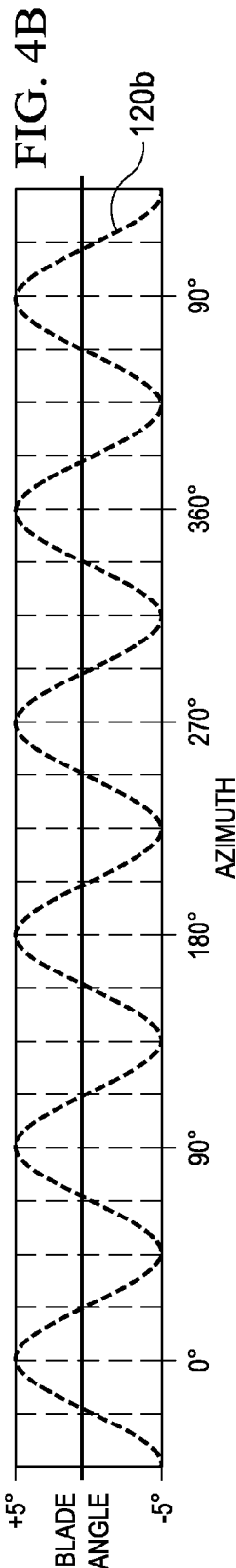
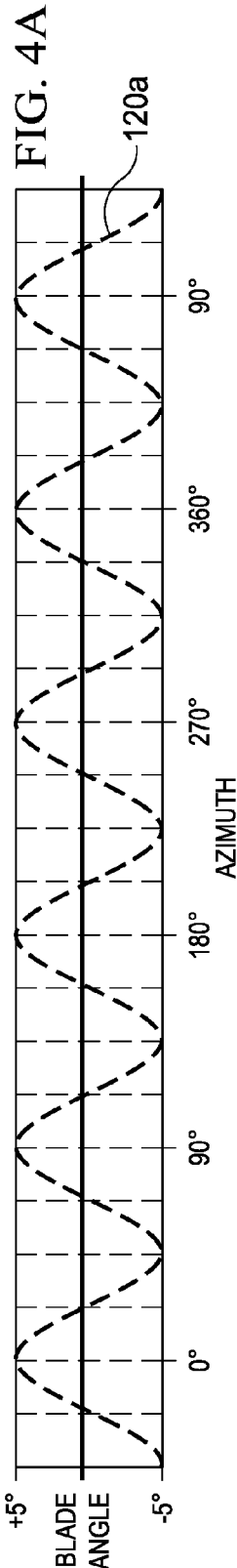
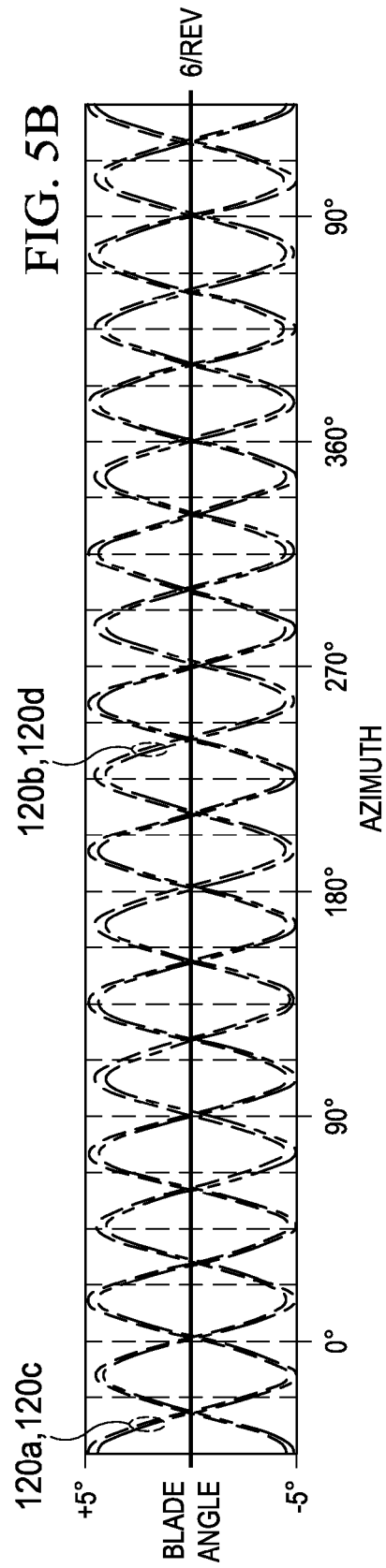
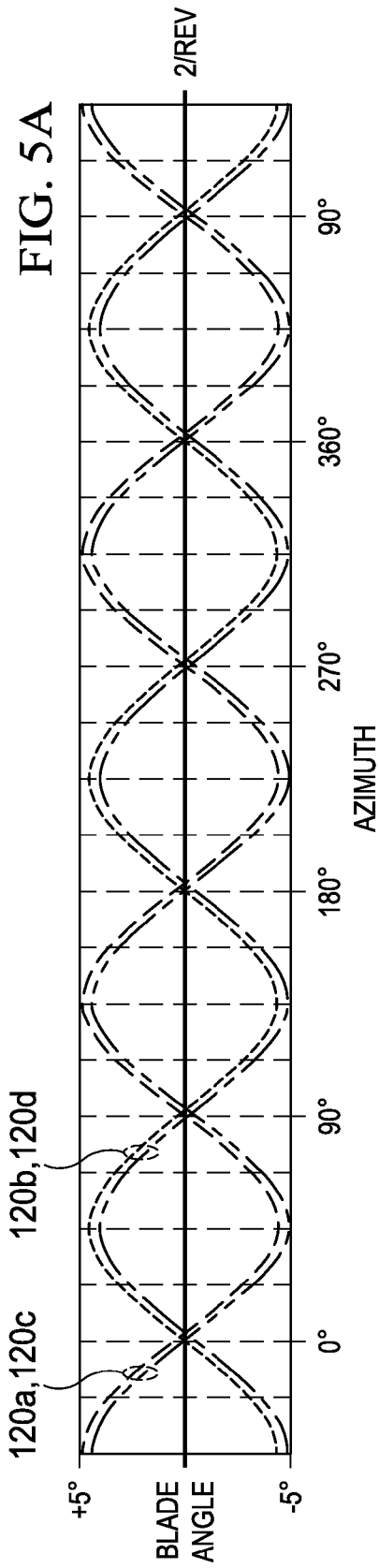


FIG. 2







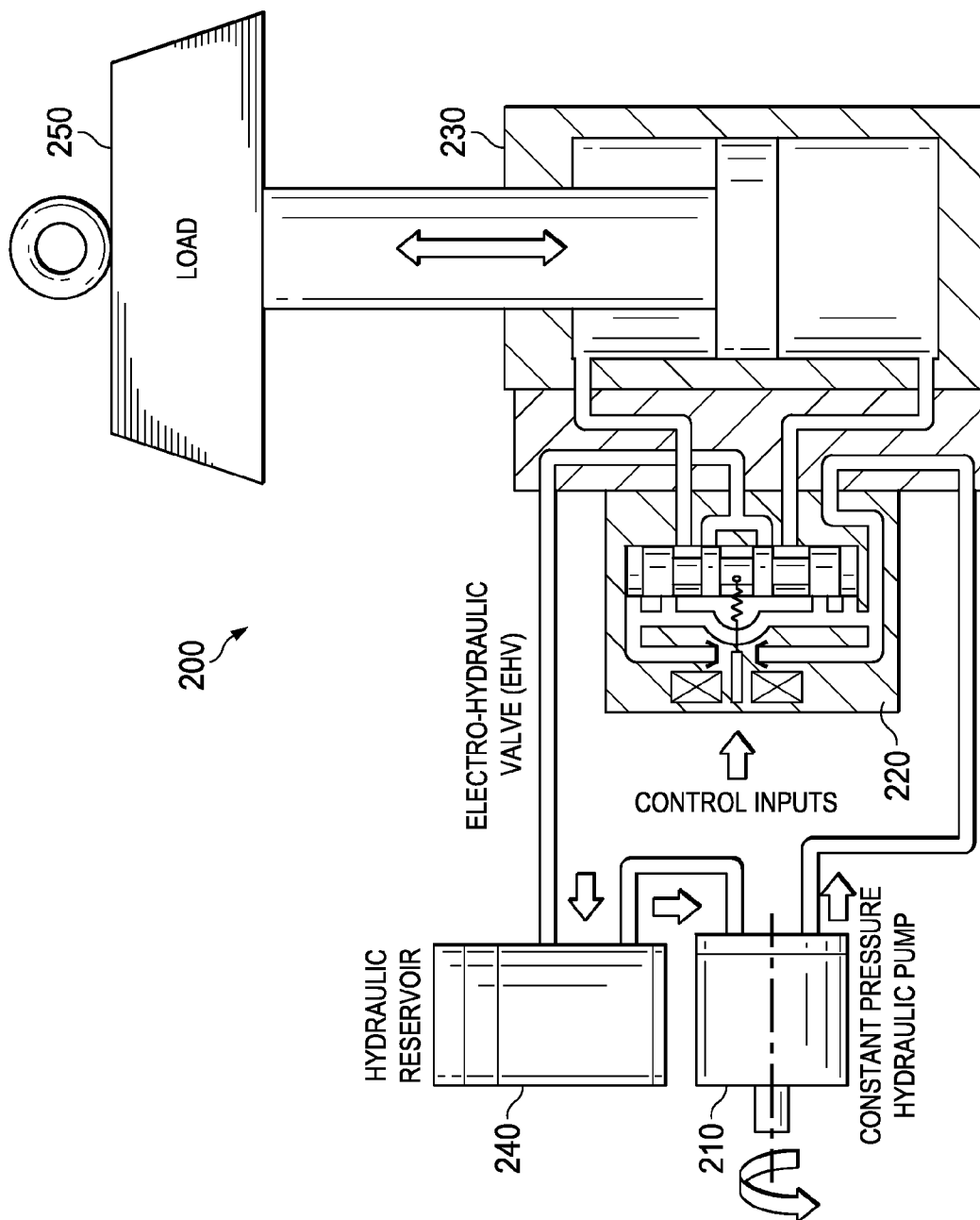


FIG. 6A  
(PRIOR ART)



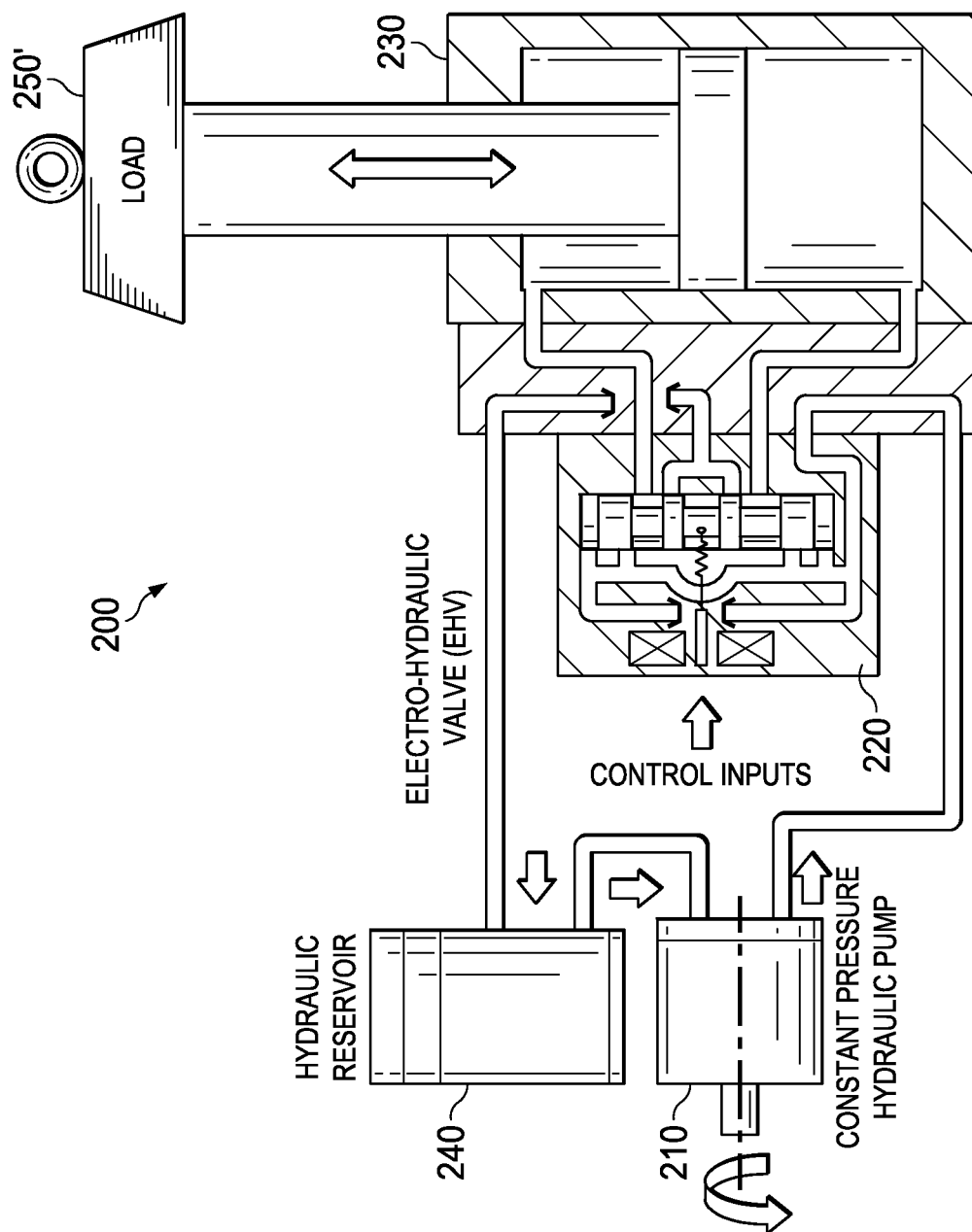
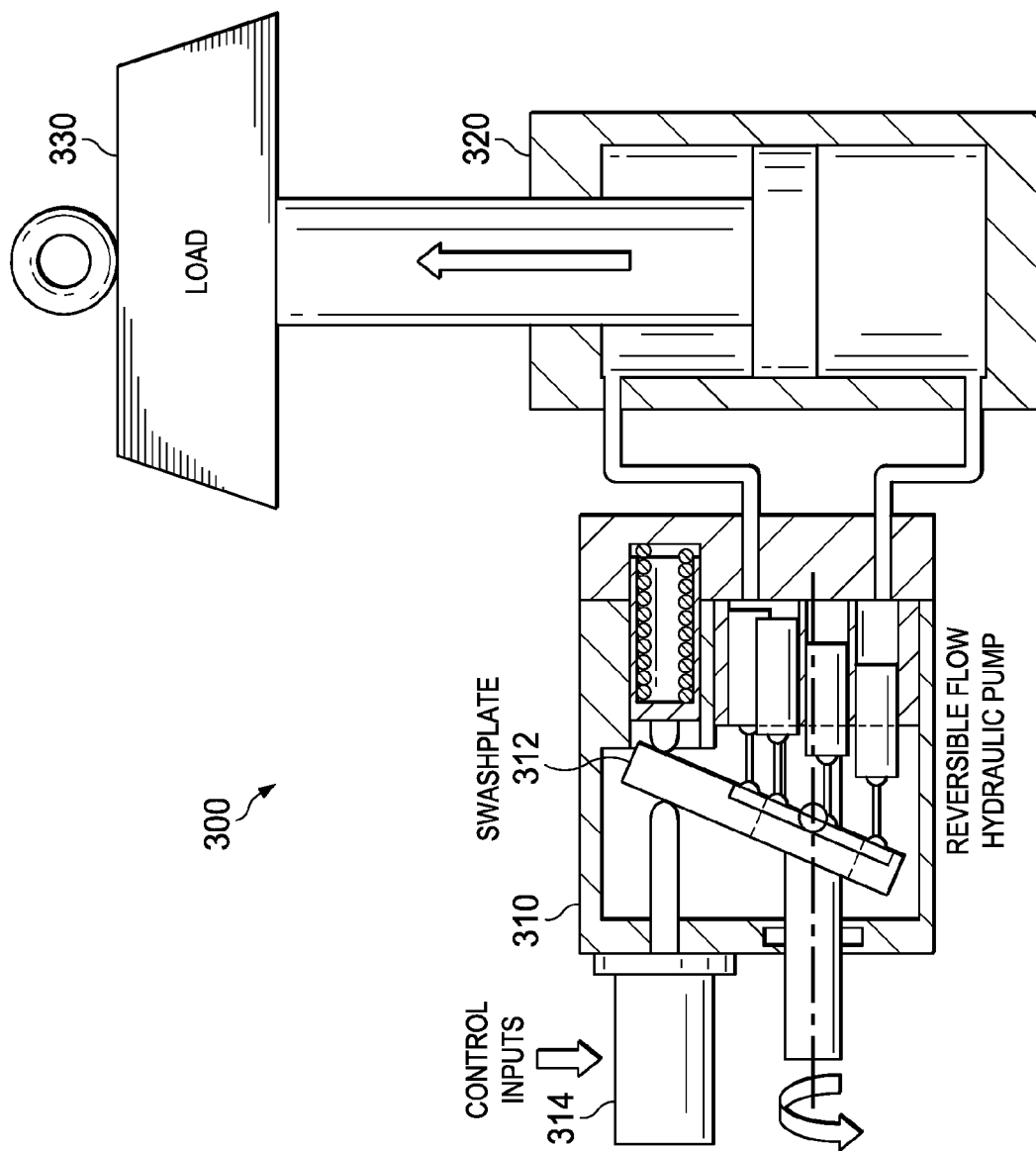
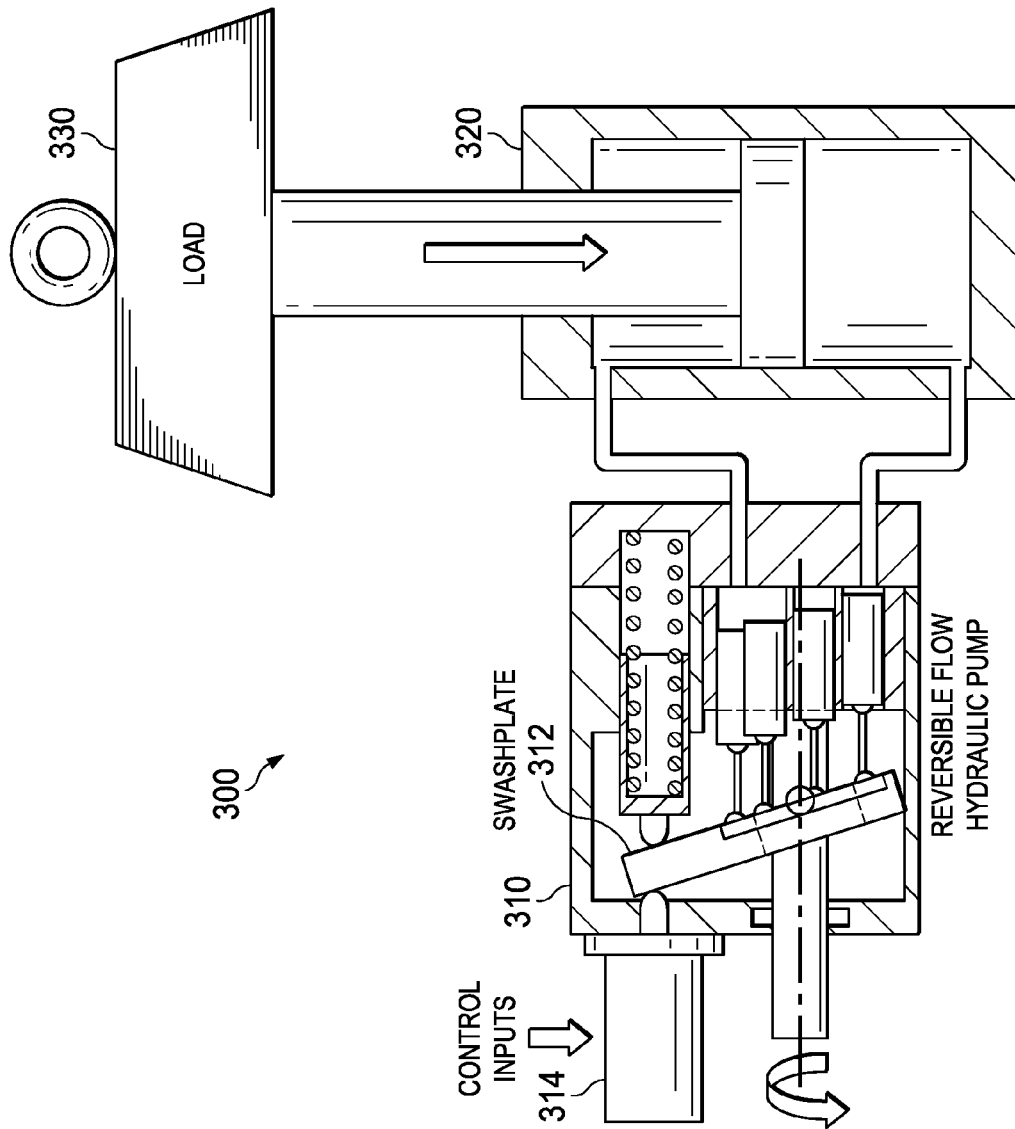


FIG. 6B  
(PRIOR ART)





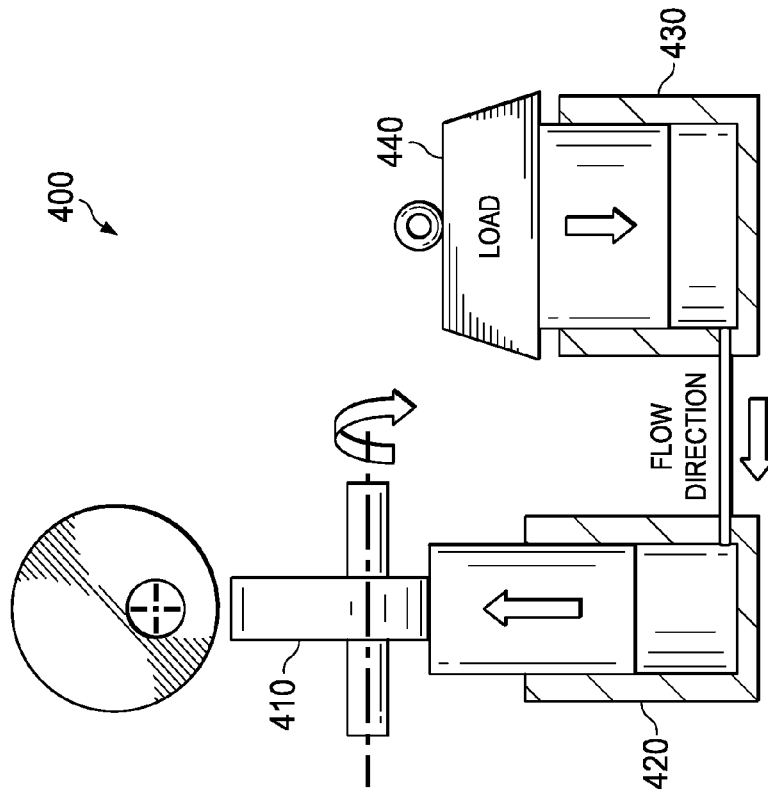


FIG. 8B

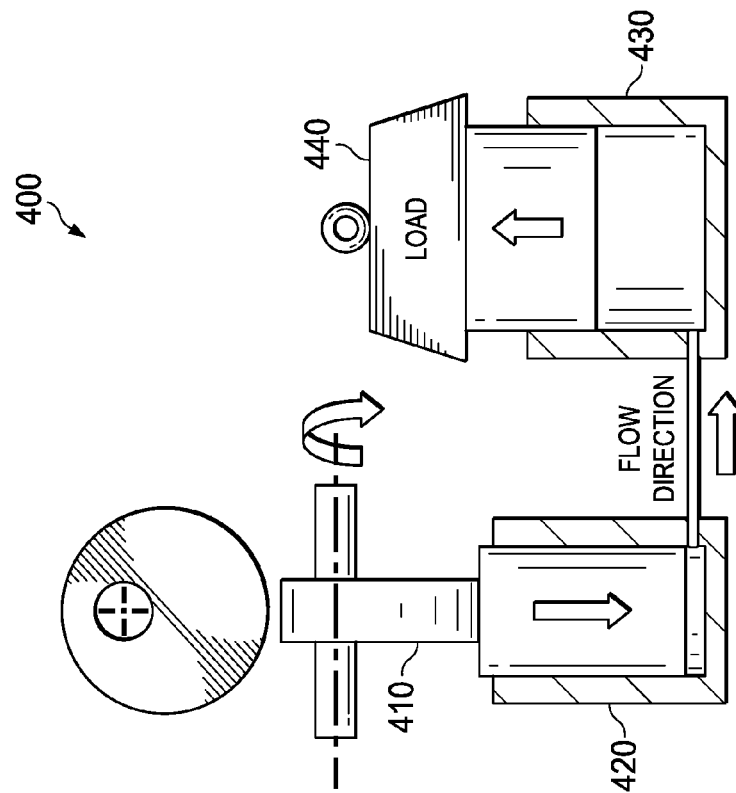


FIG. 8A

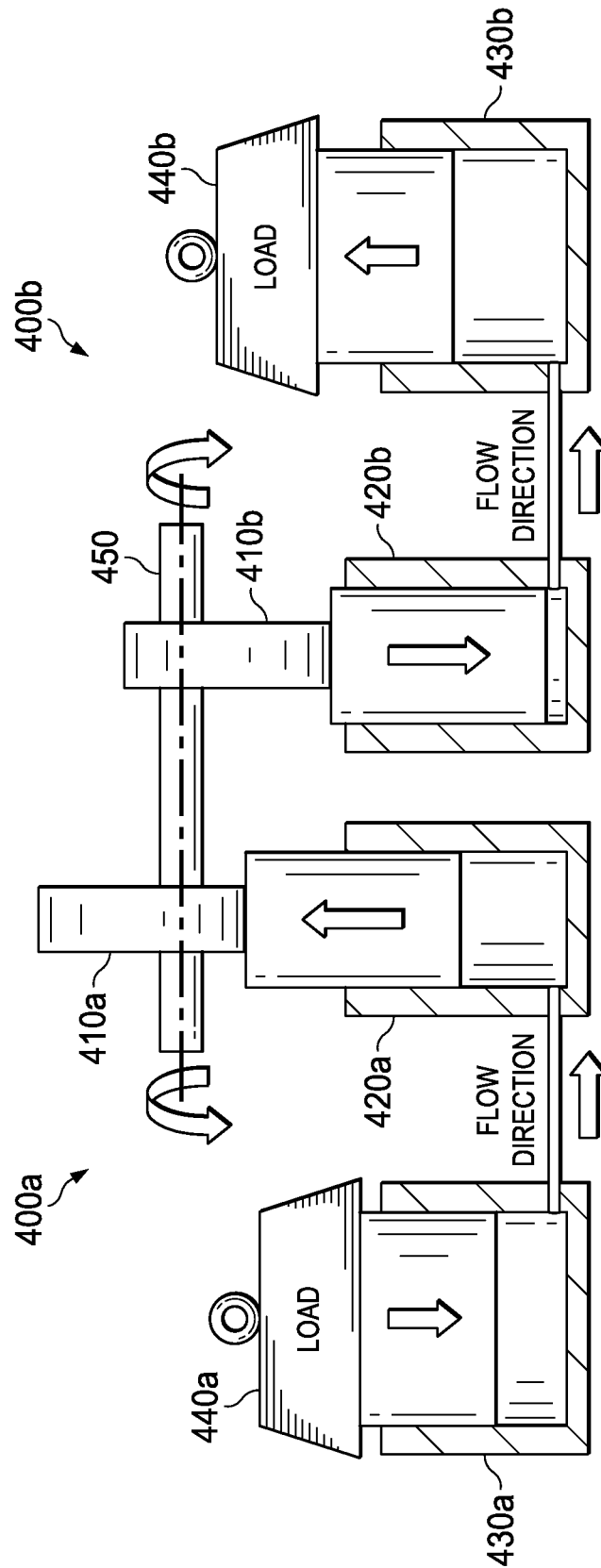


FIG. 8C

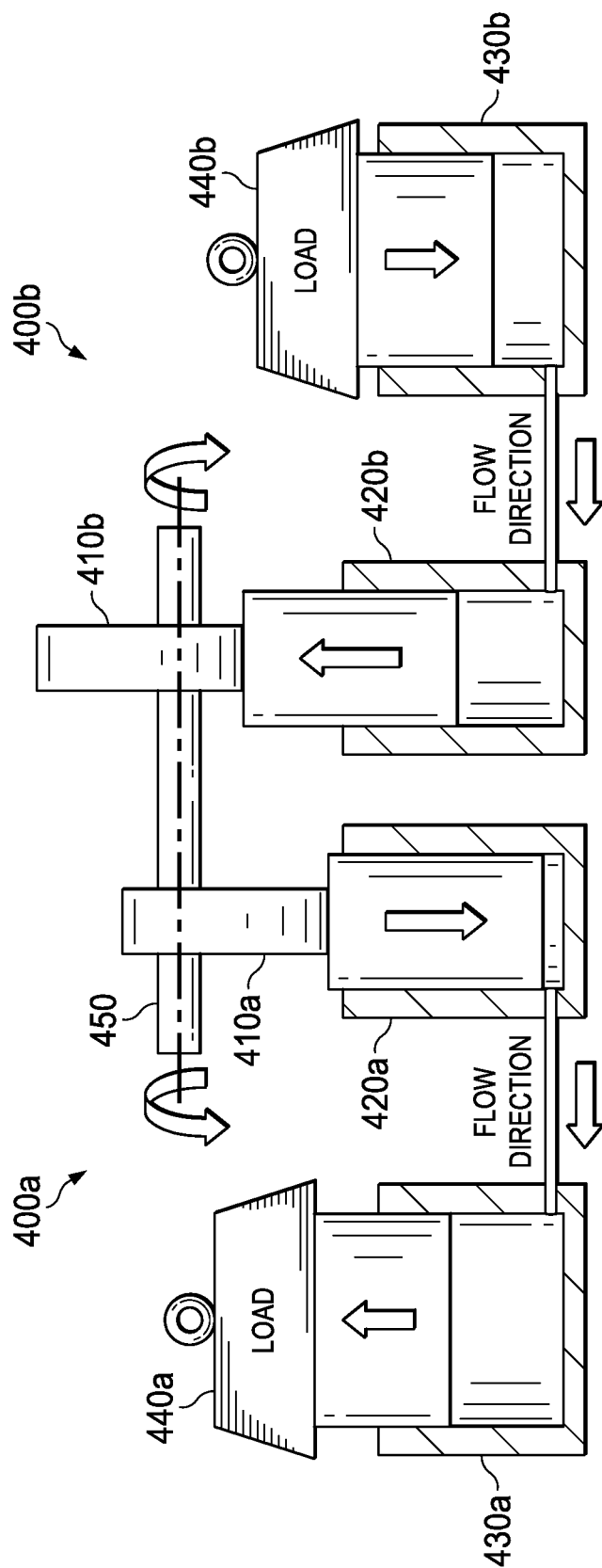
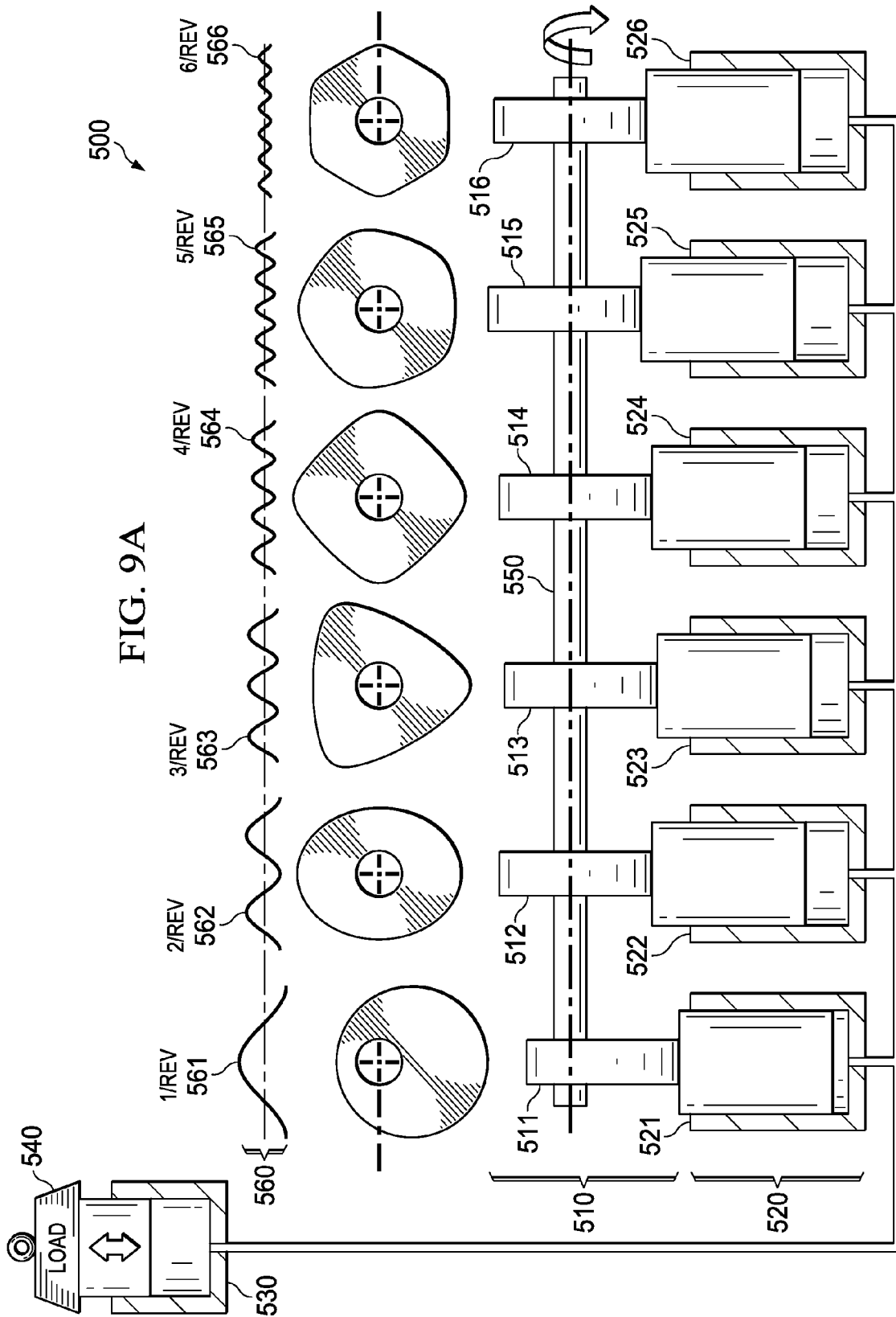
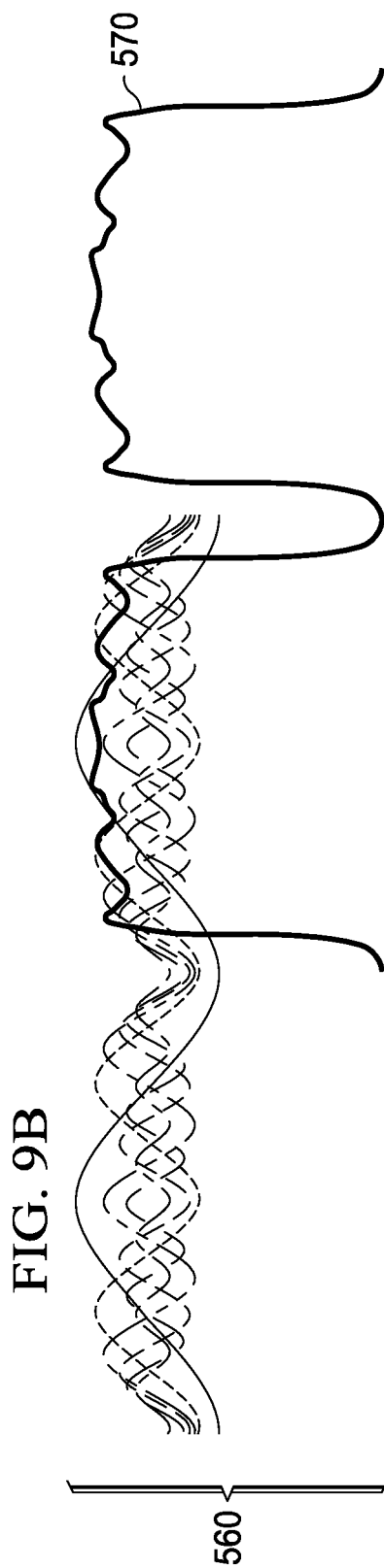
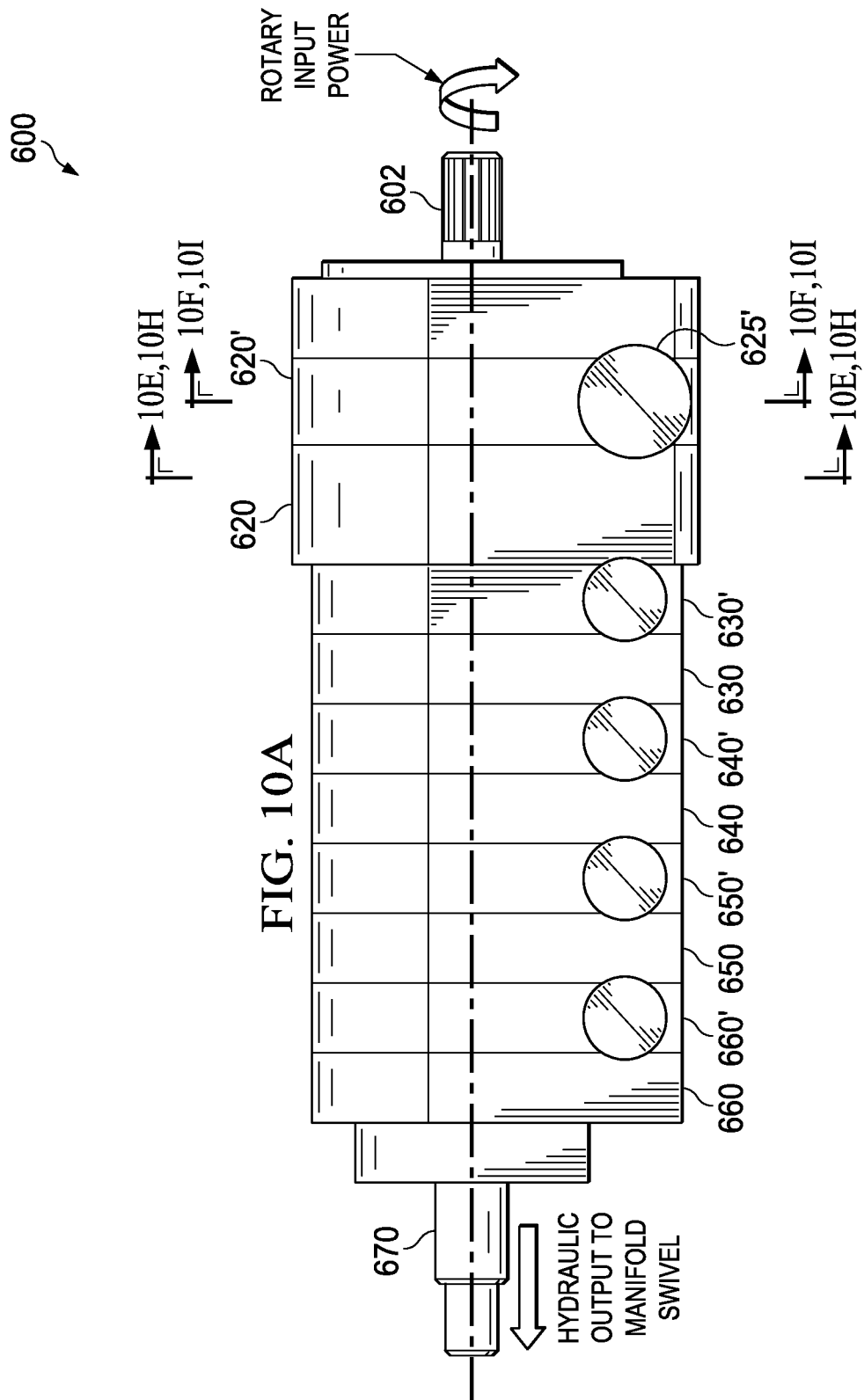


FIG. 8D









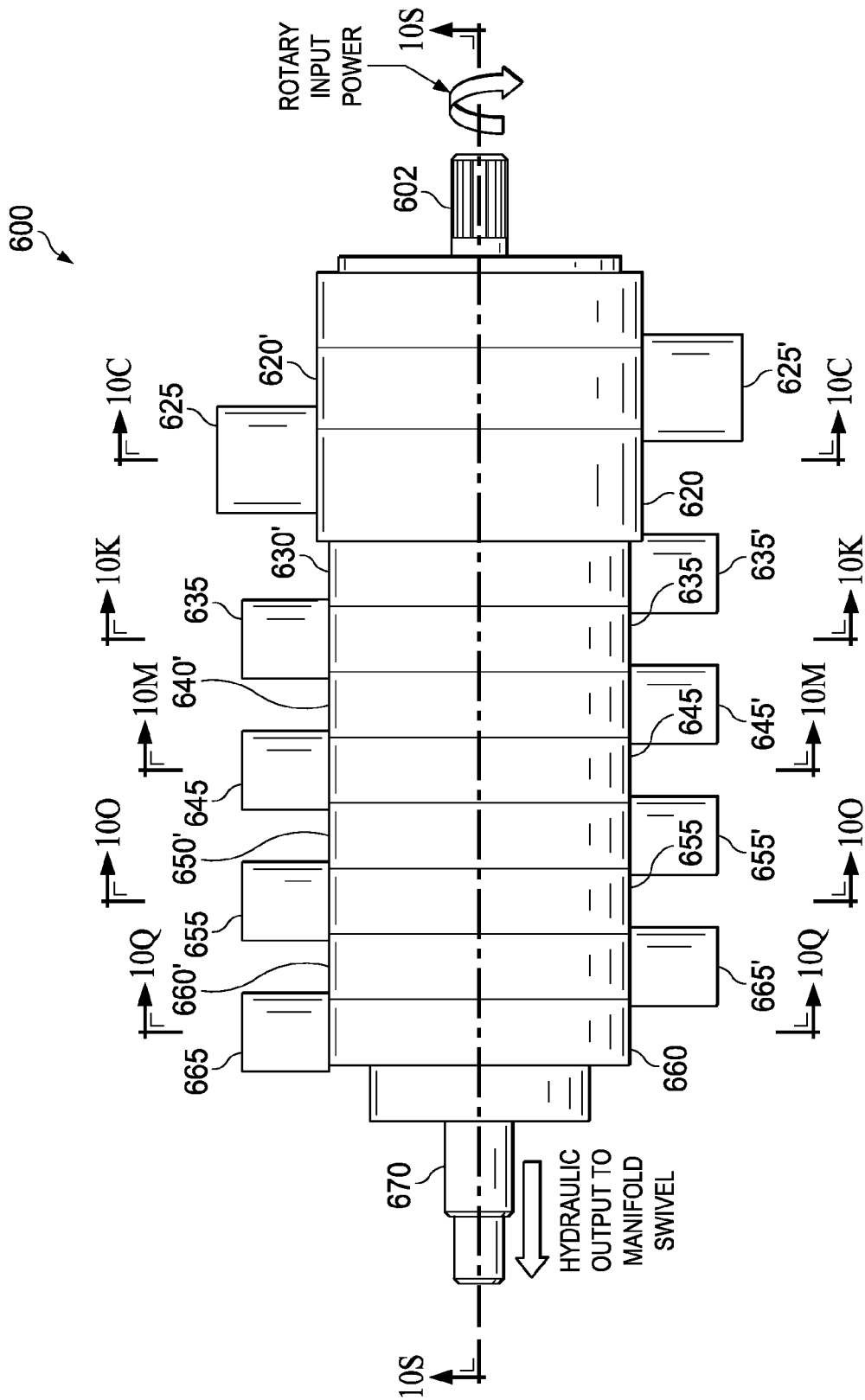
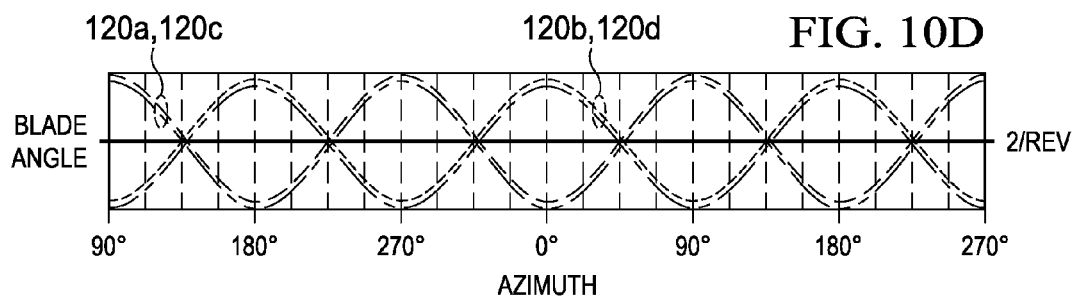
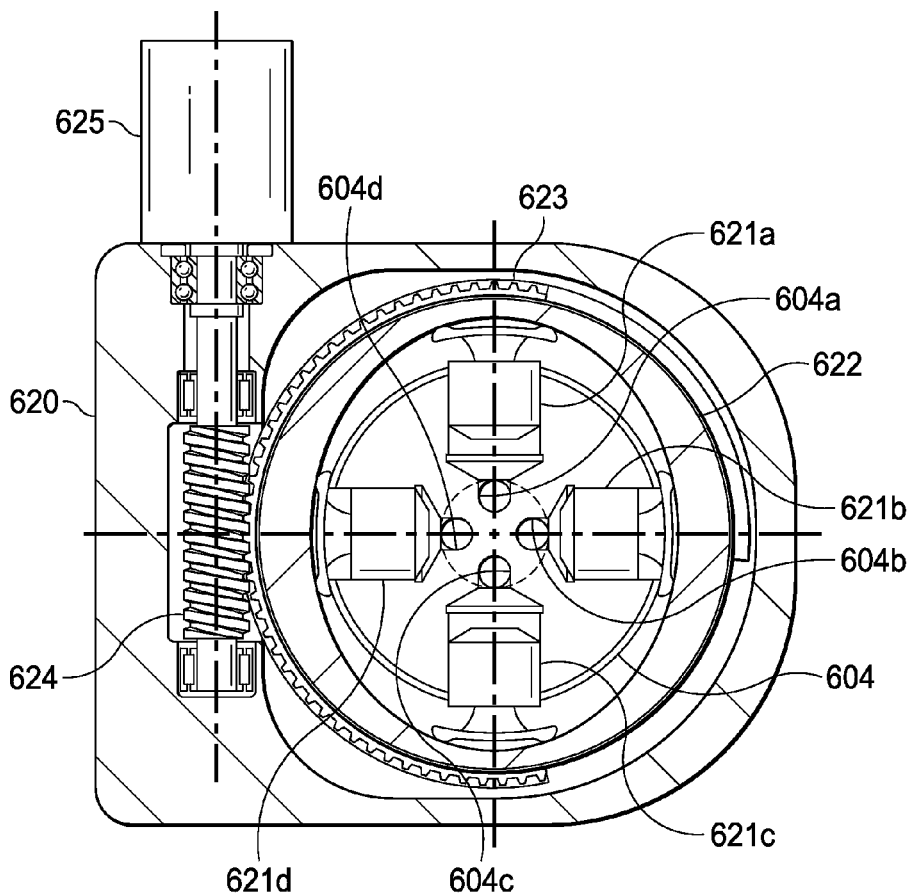


FIG. 10B

FIG. 10C



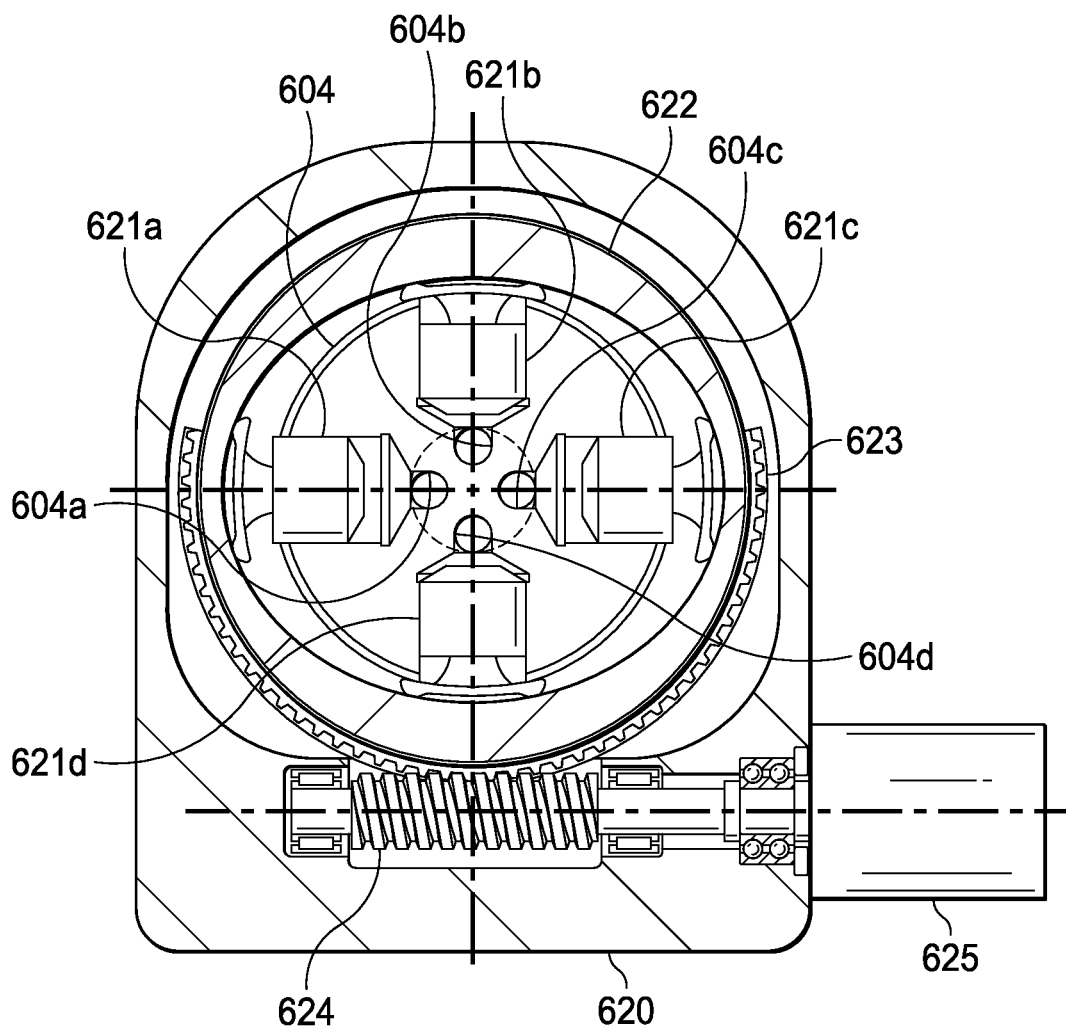


FIG. 10E

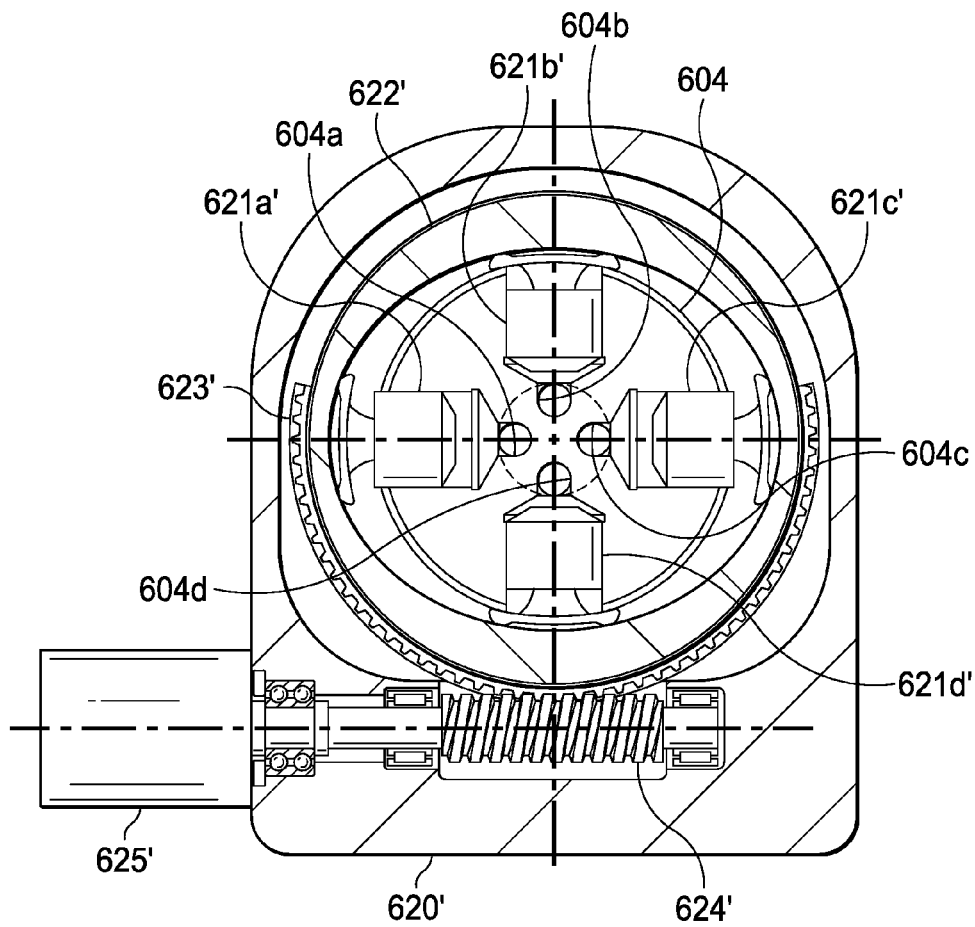
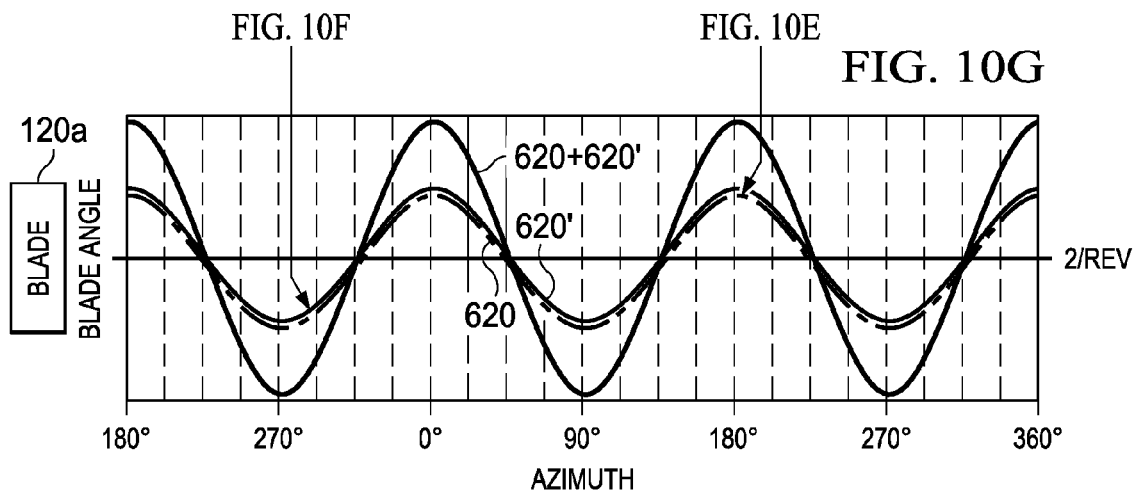


FIG. 10F



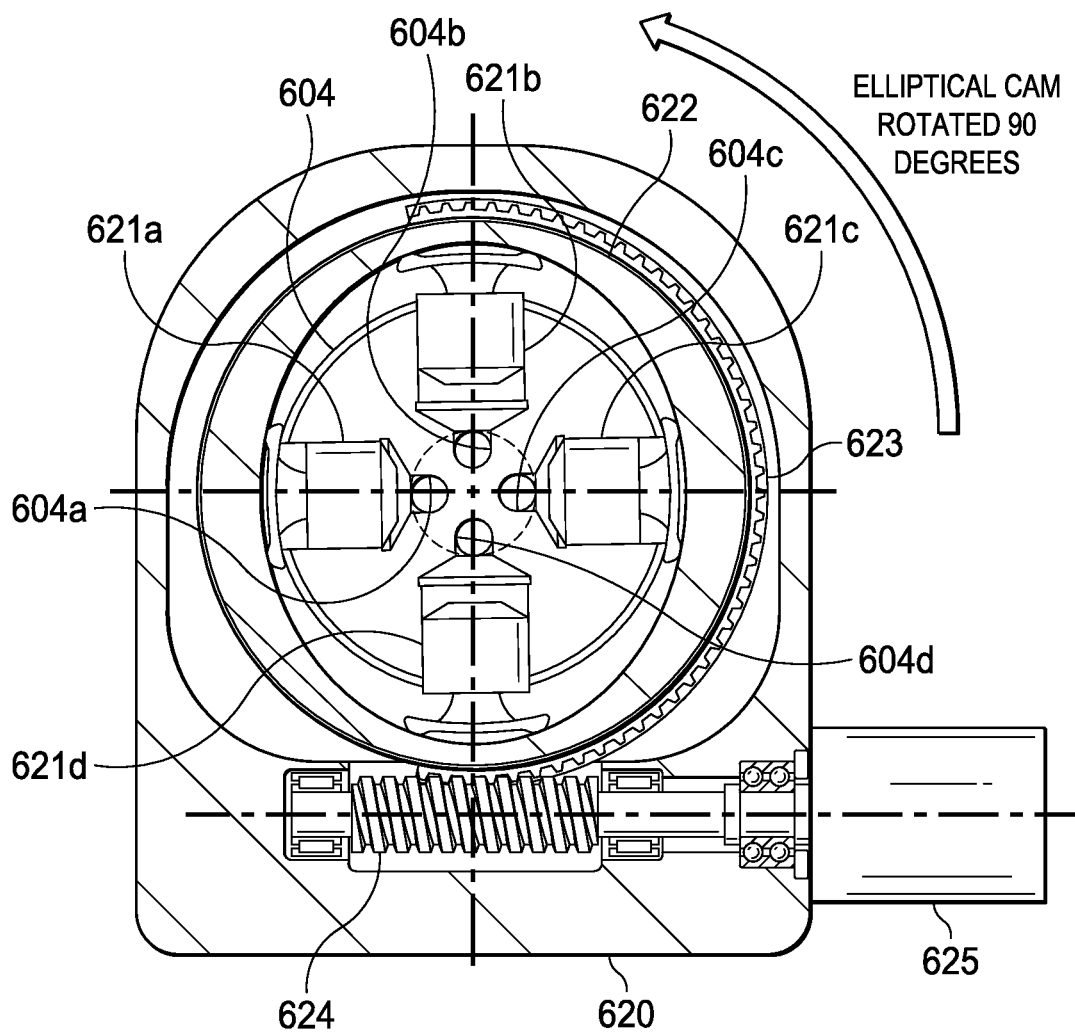


FIG. 10H

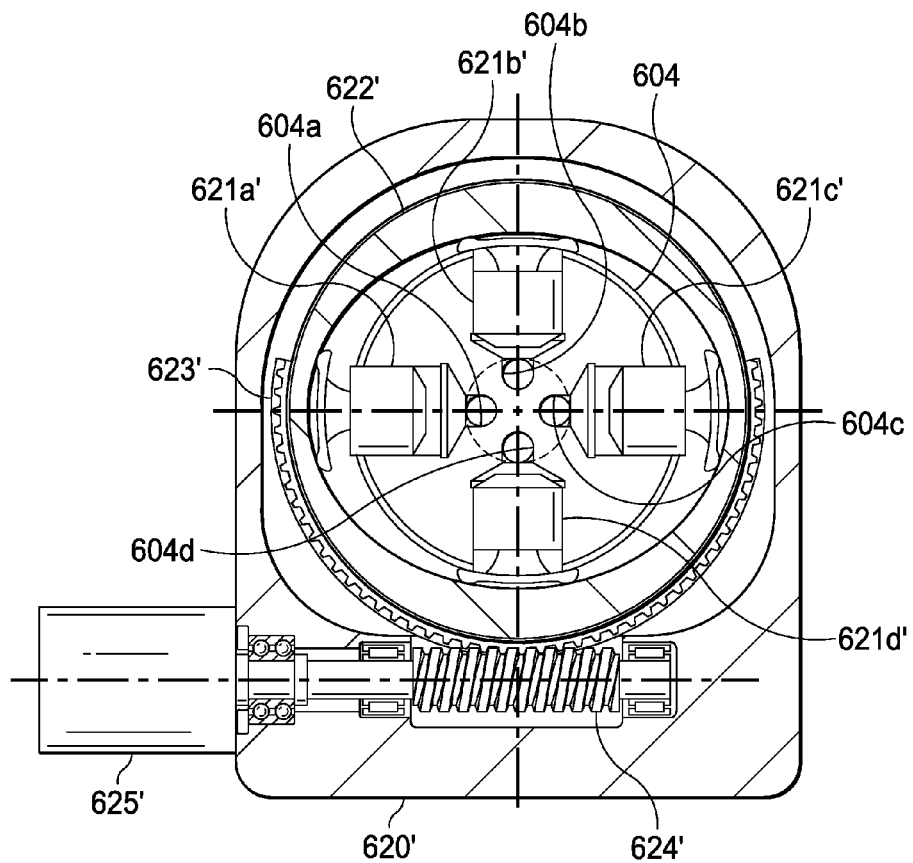


FIG. 10I

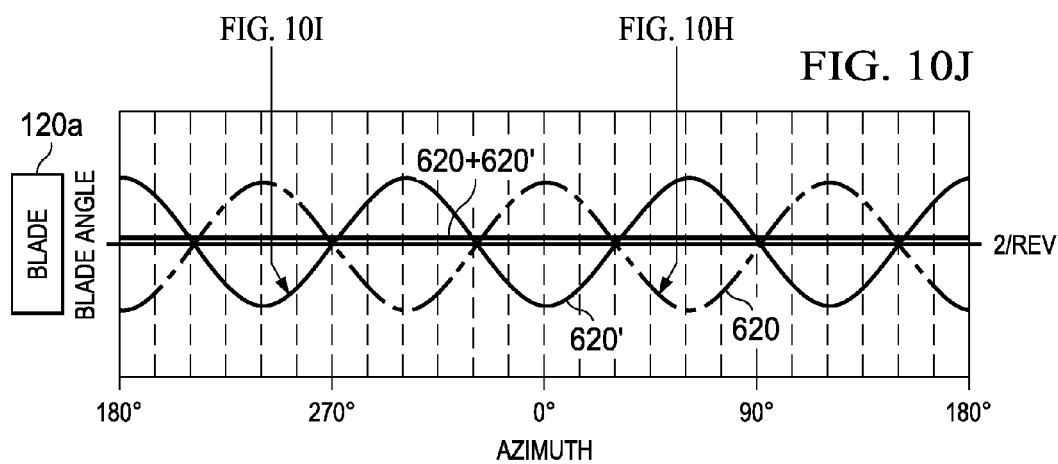


FIG. 10K

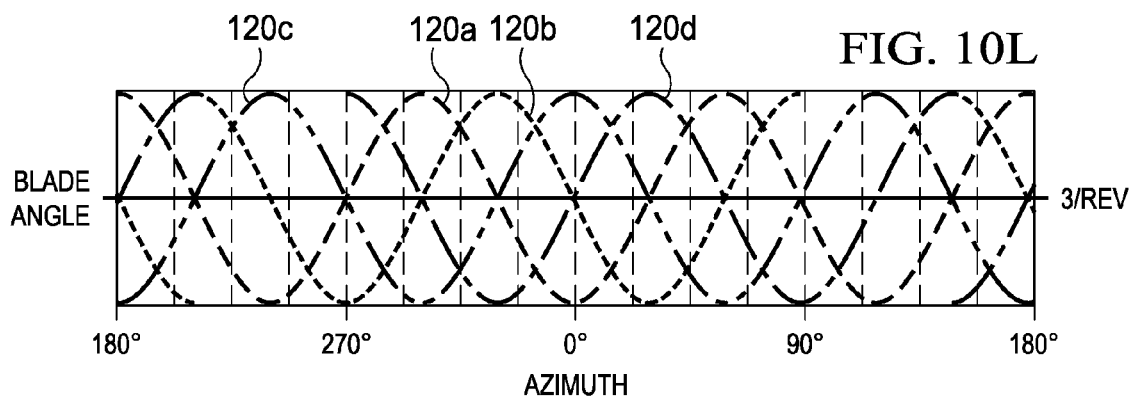
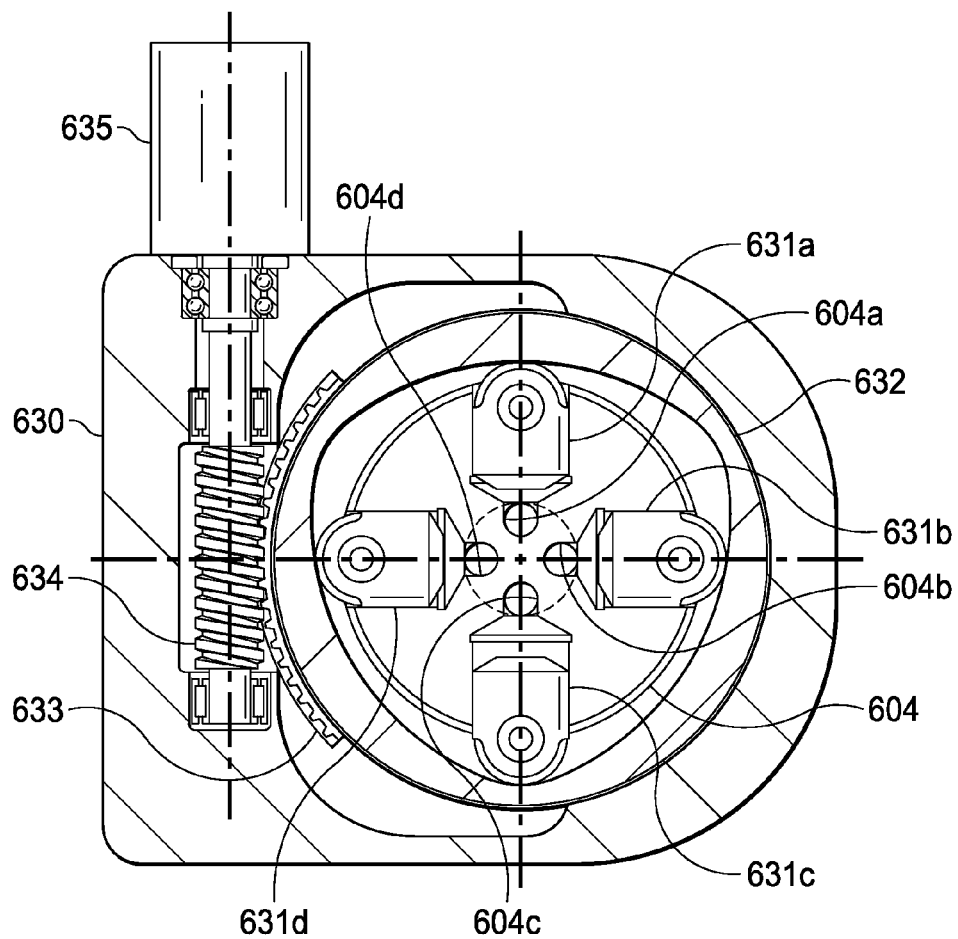




FIG. 10M

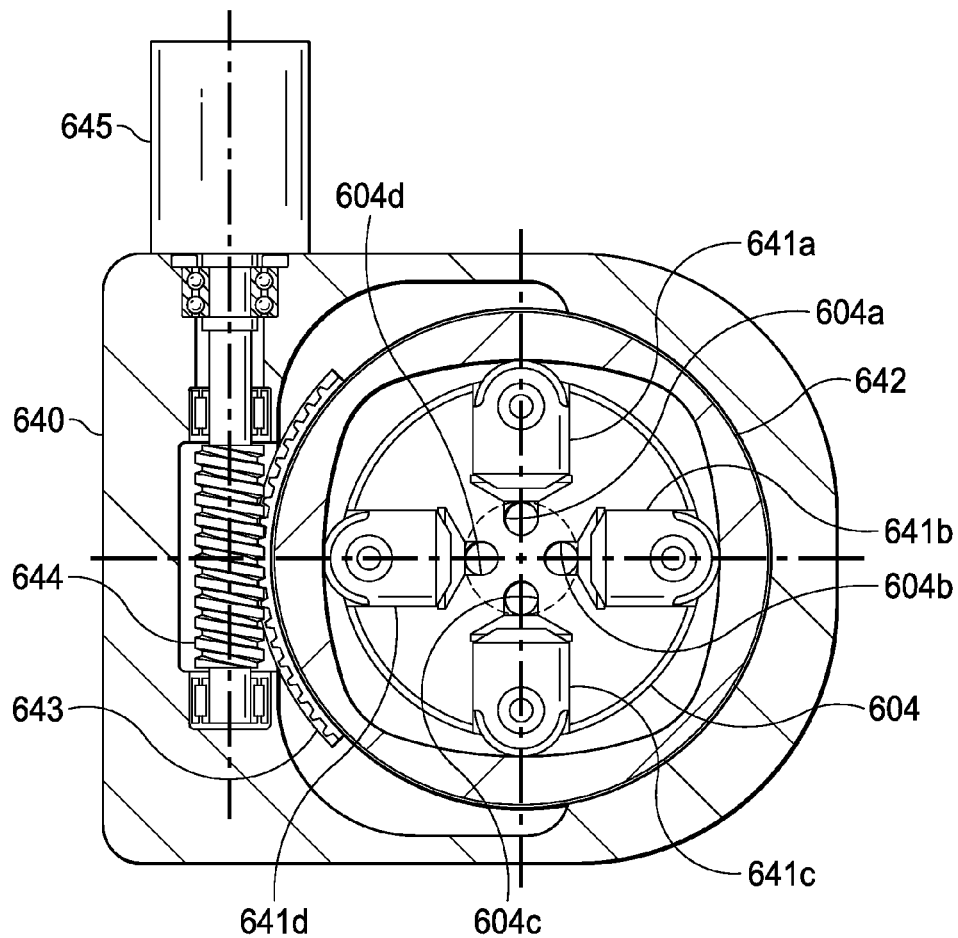


FIG. 10N

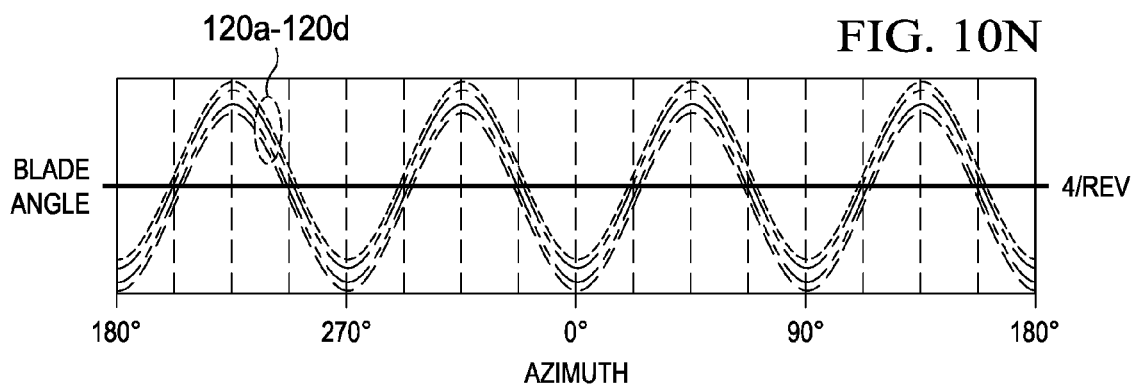


FIG. 10O

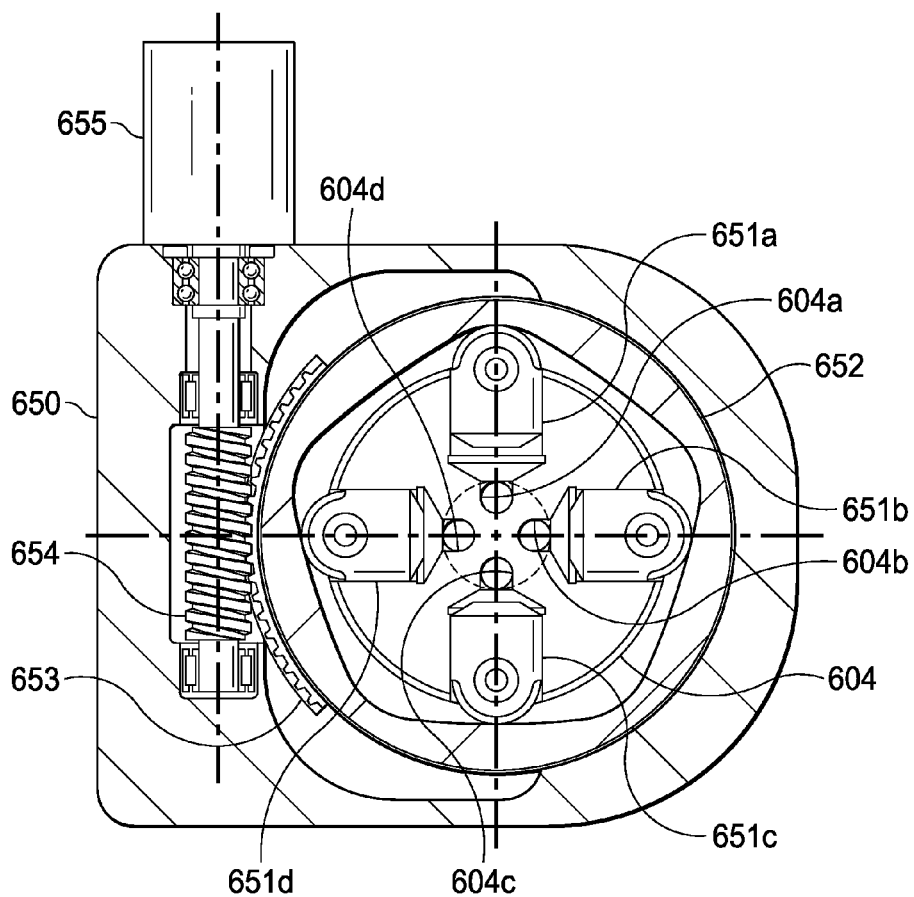


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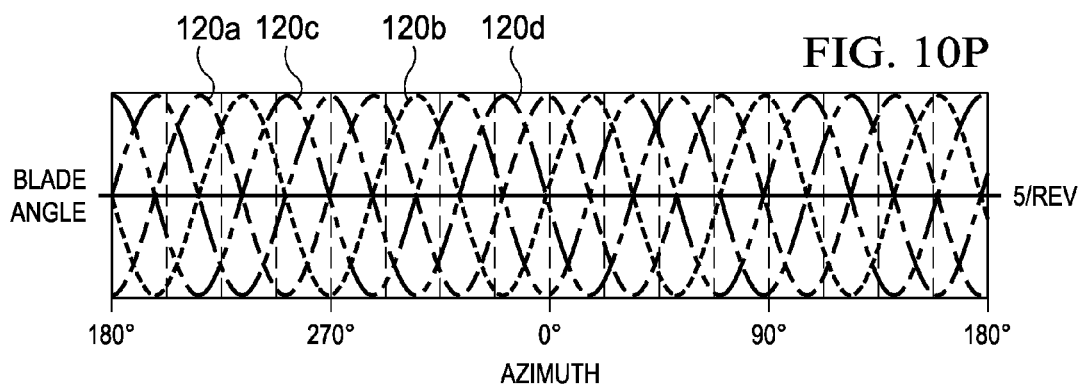


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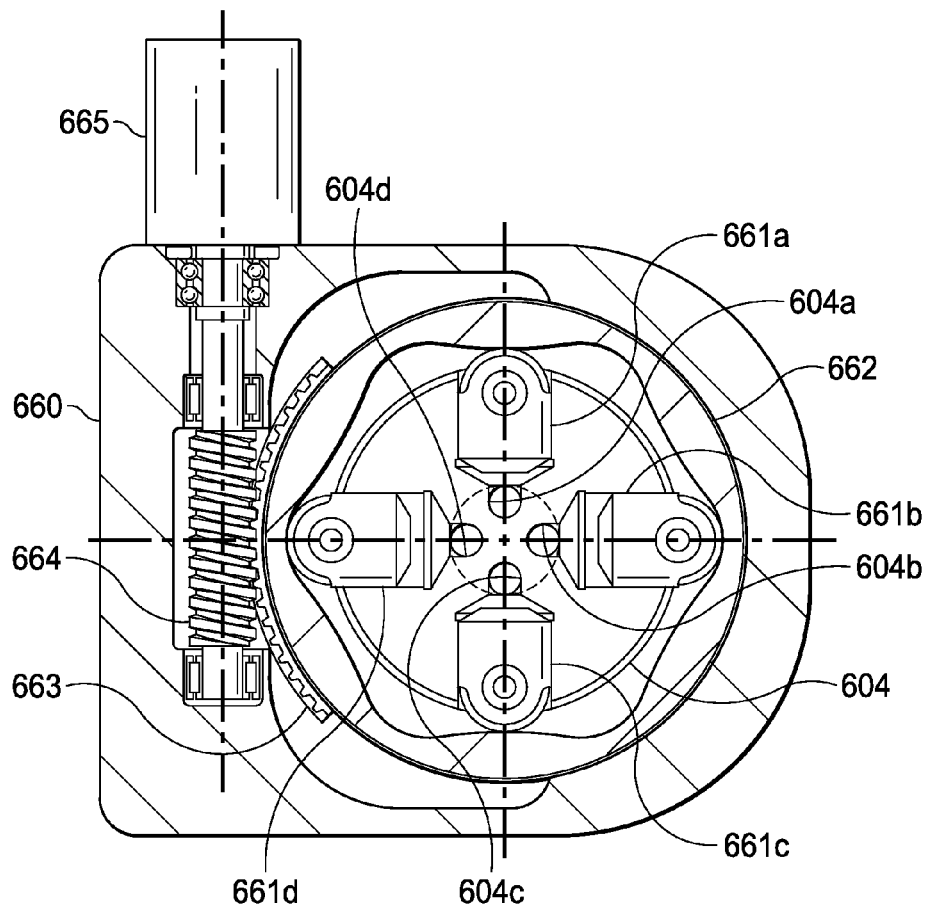
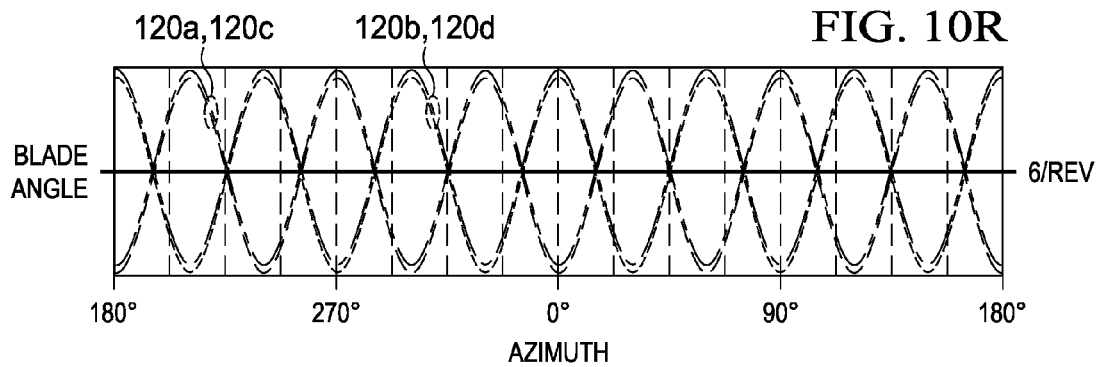


FIG. 10R



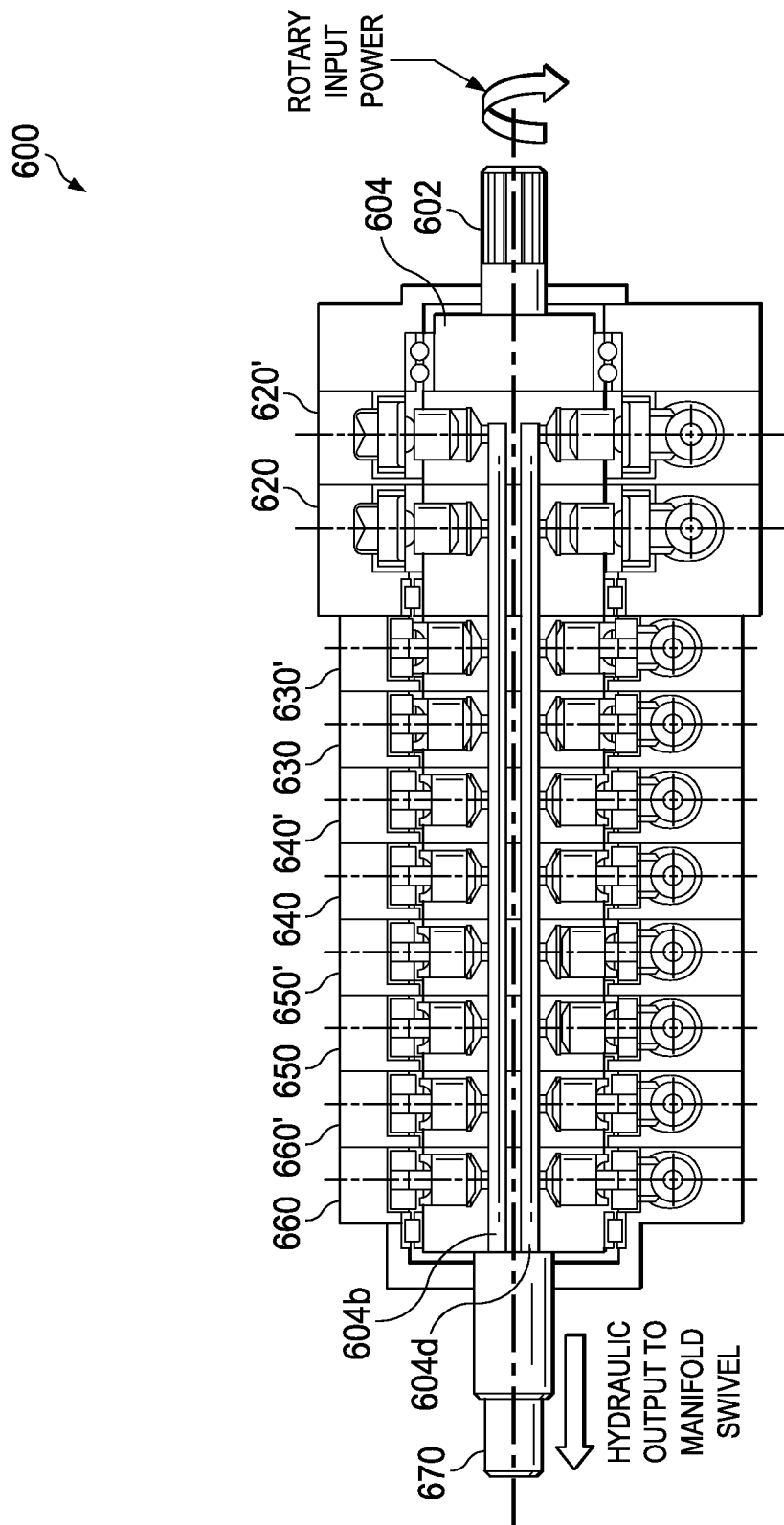


FIG. 10S

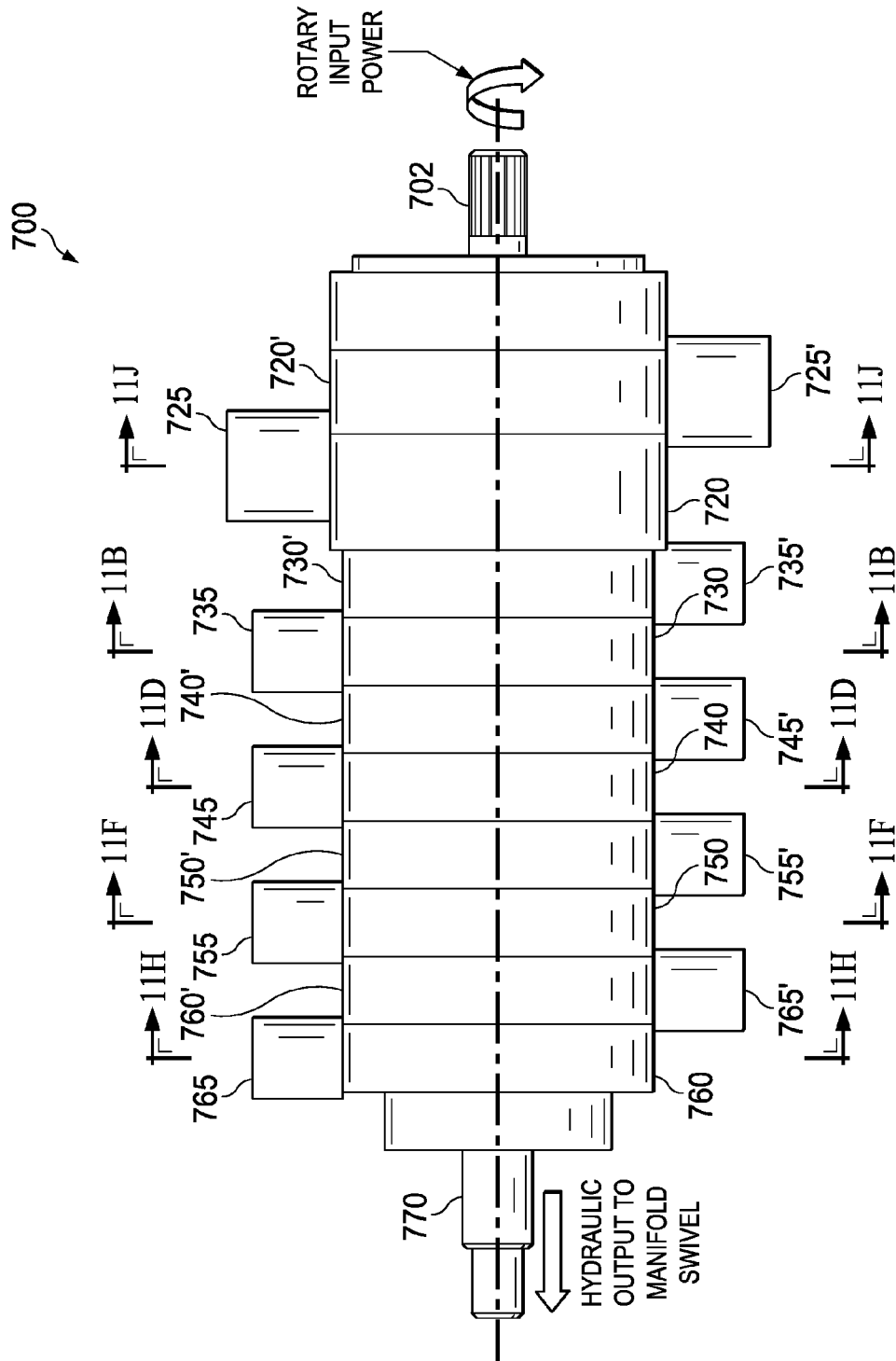


FIG. 11A

FIG. 11B

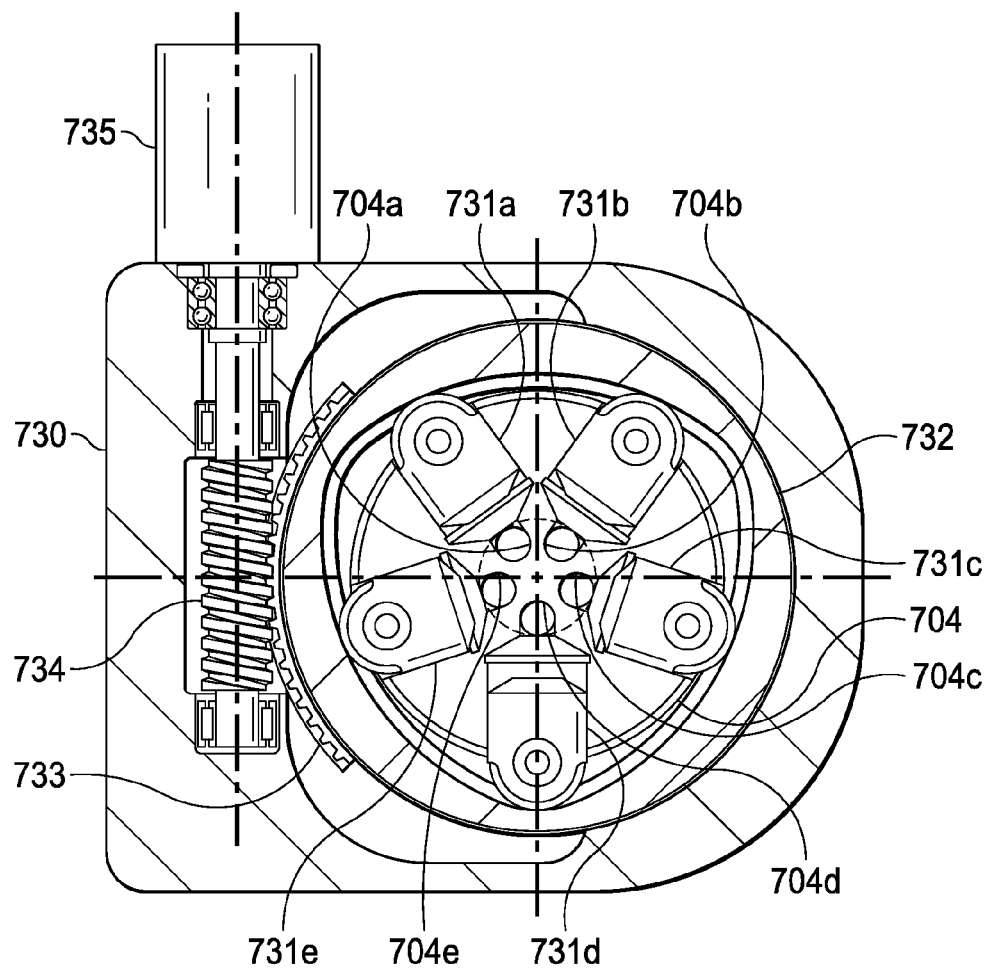


FIG. 11C

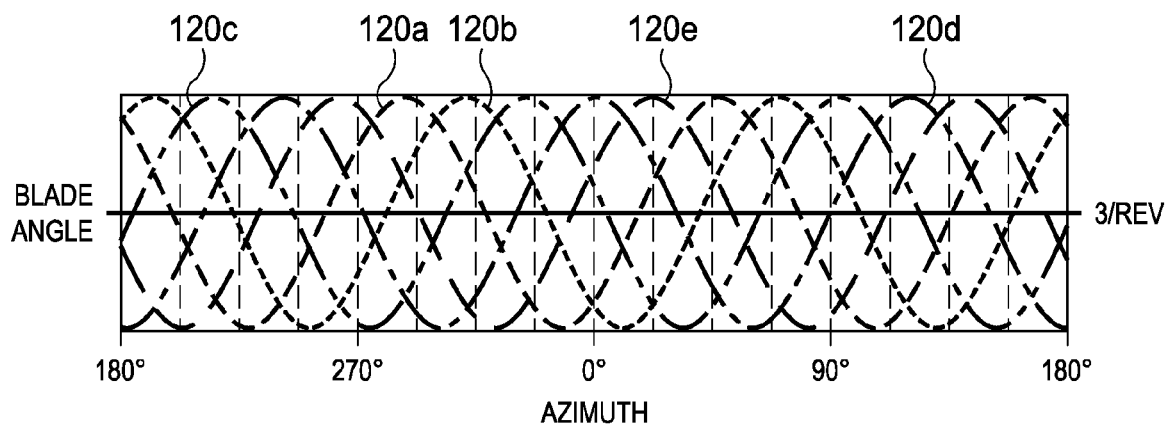


FIG. 11D

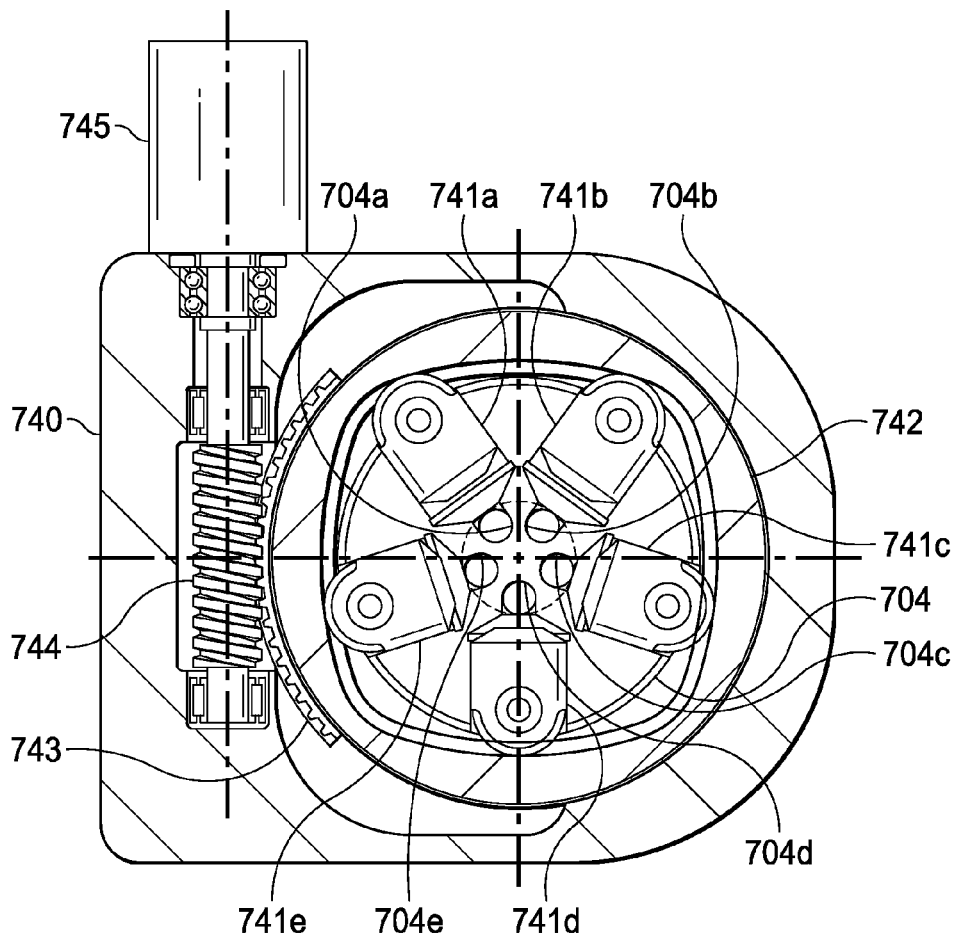


FIG. 11E

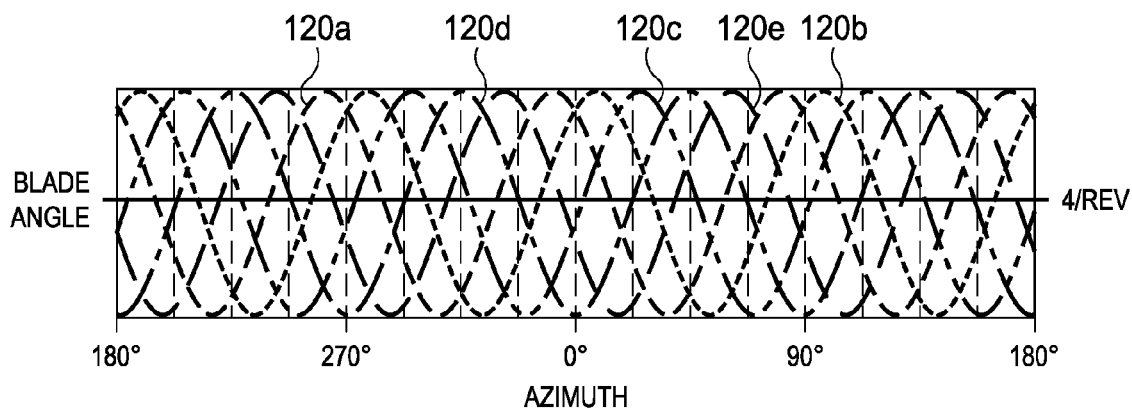


FIG. 11F

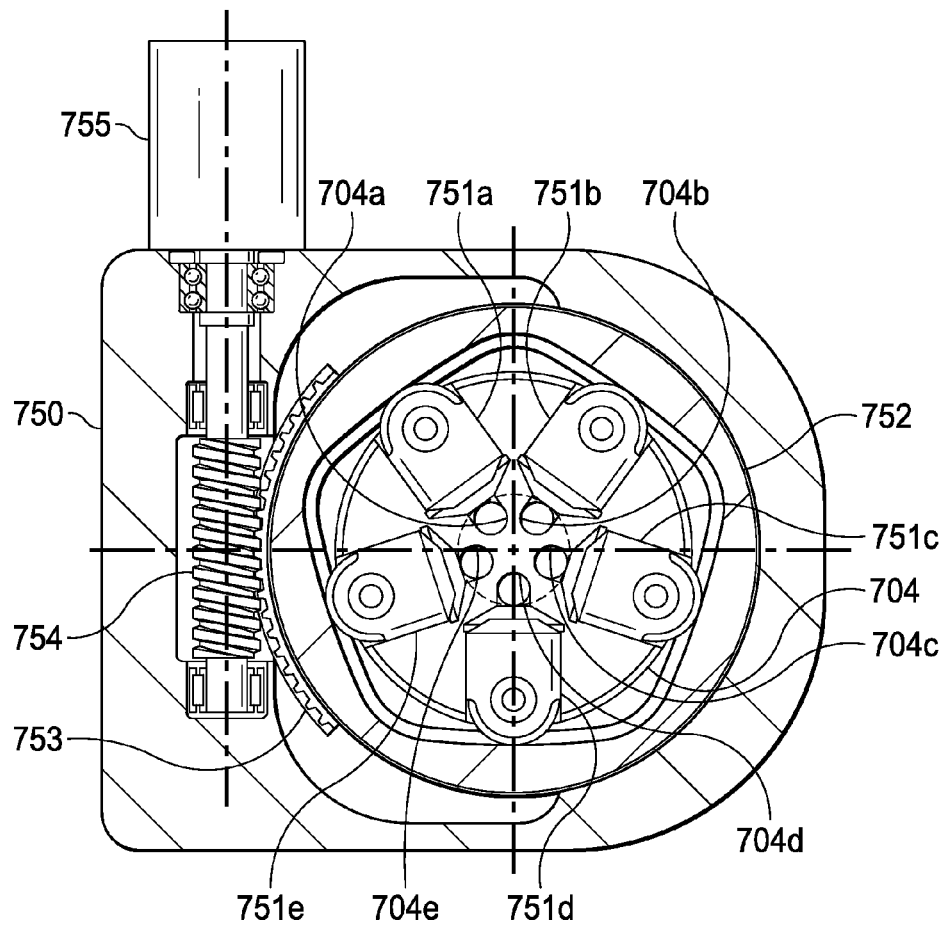


FIG. 11G

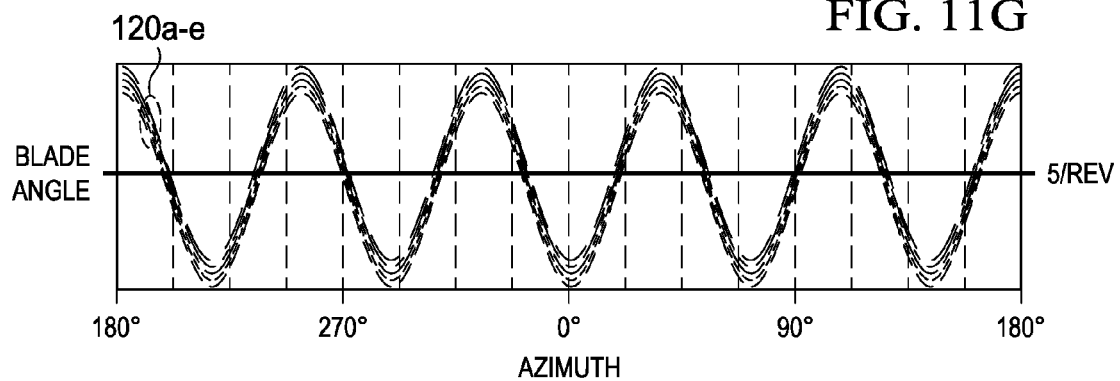




FIG. 11H

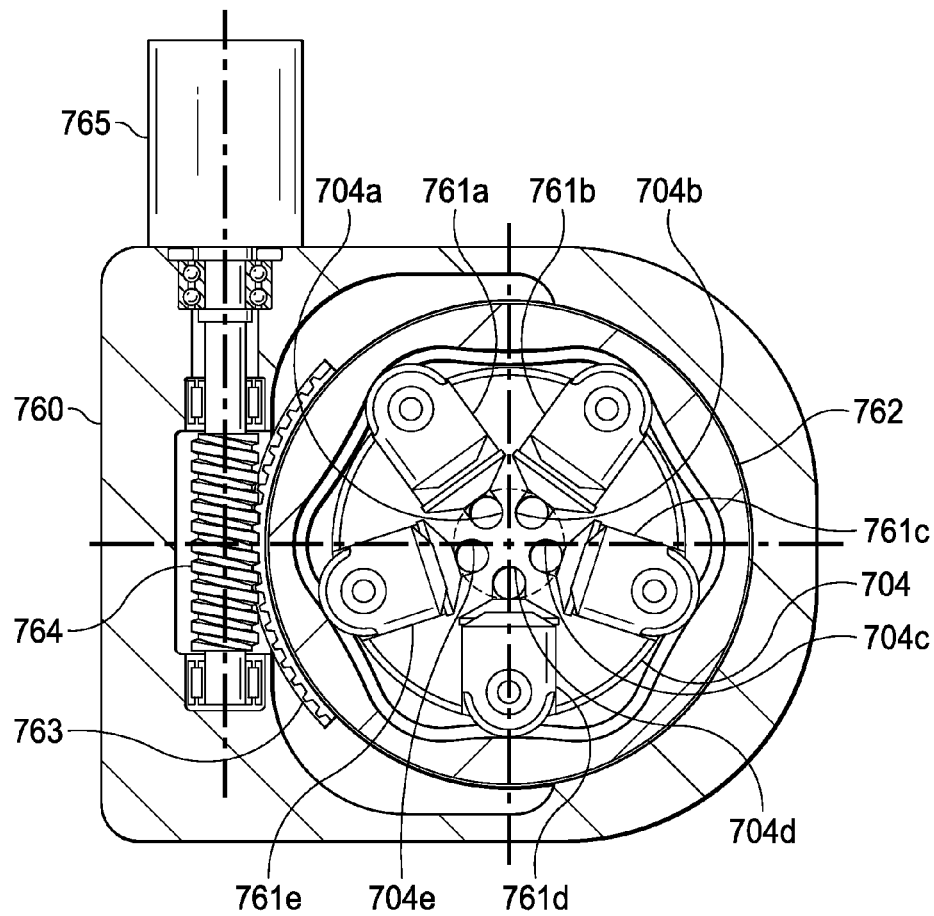


FIG. 11I

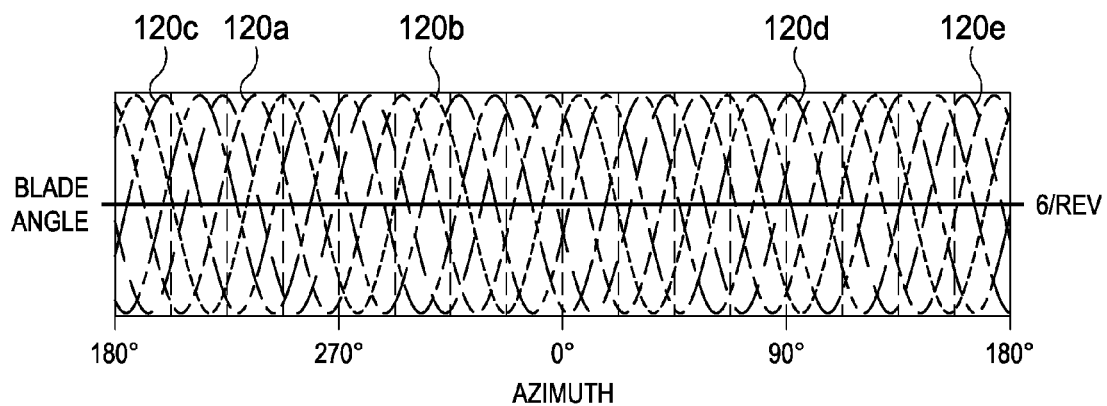


FIG. 11J

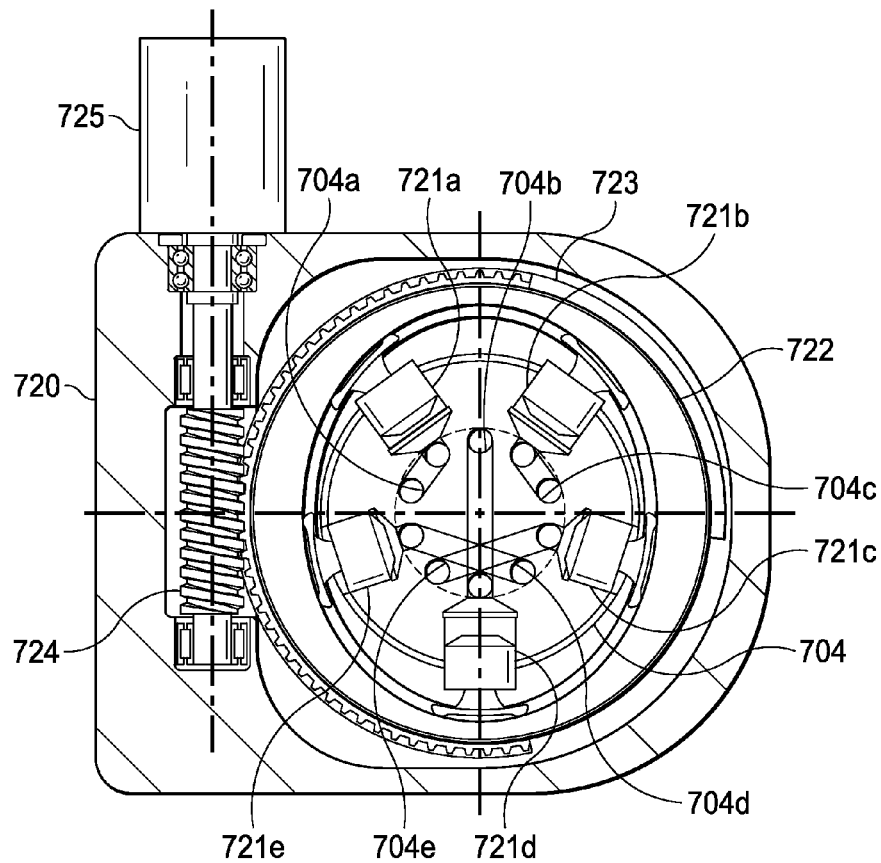
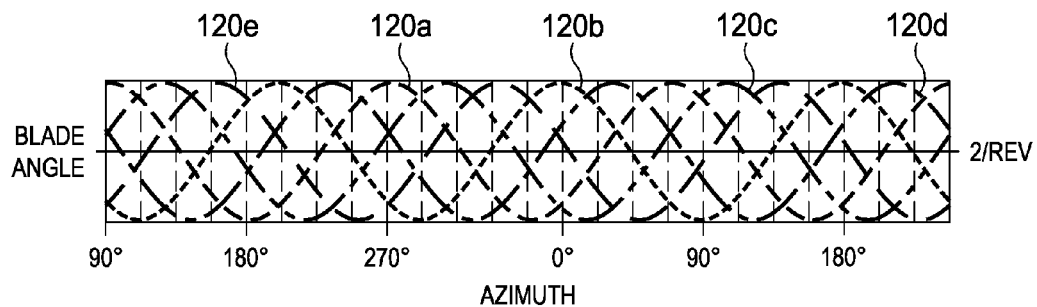
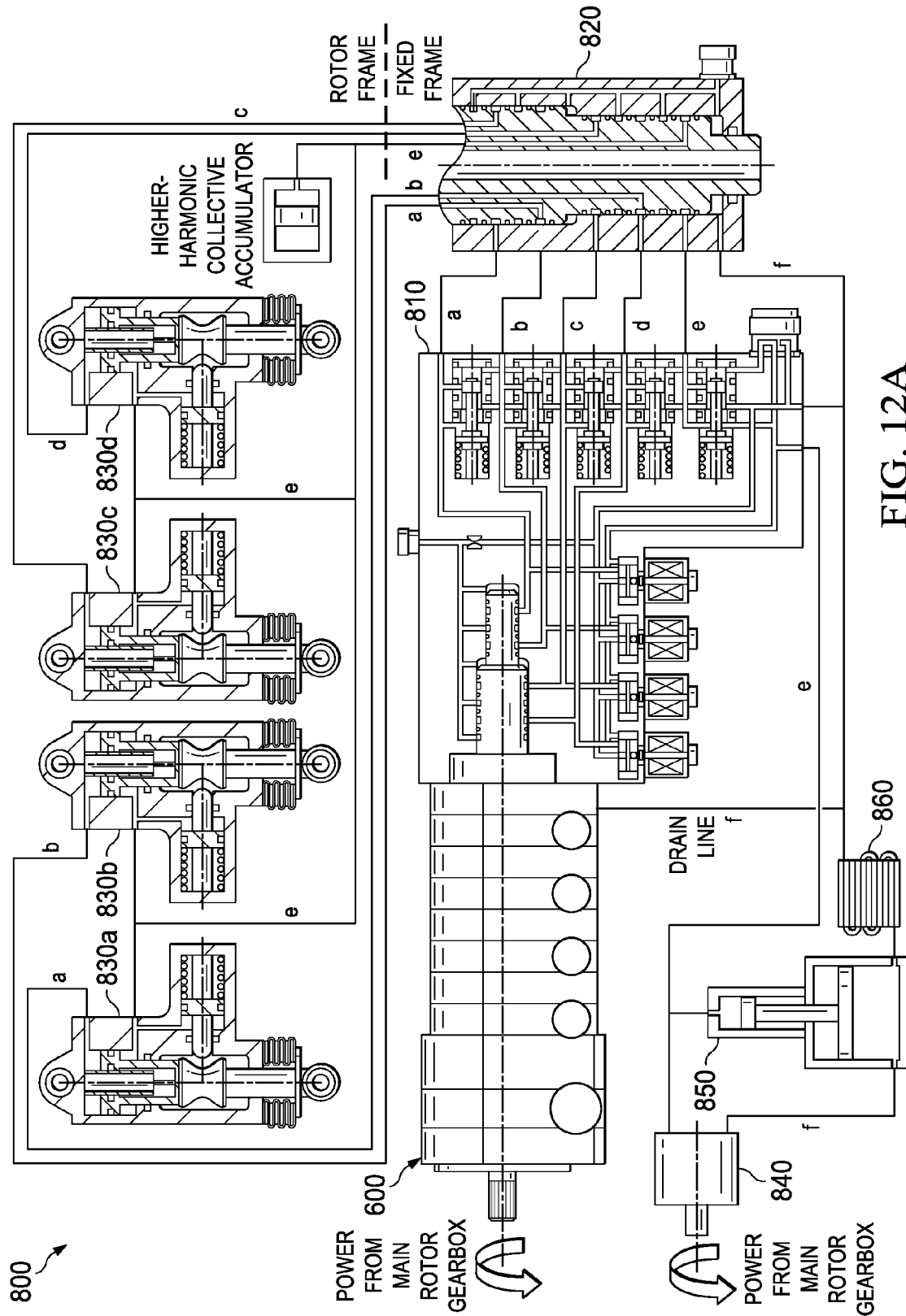


FIG. 11K





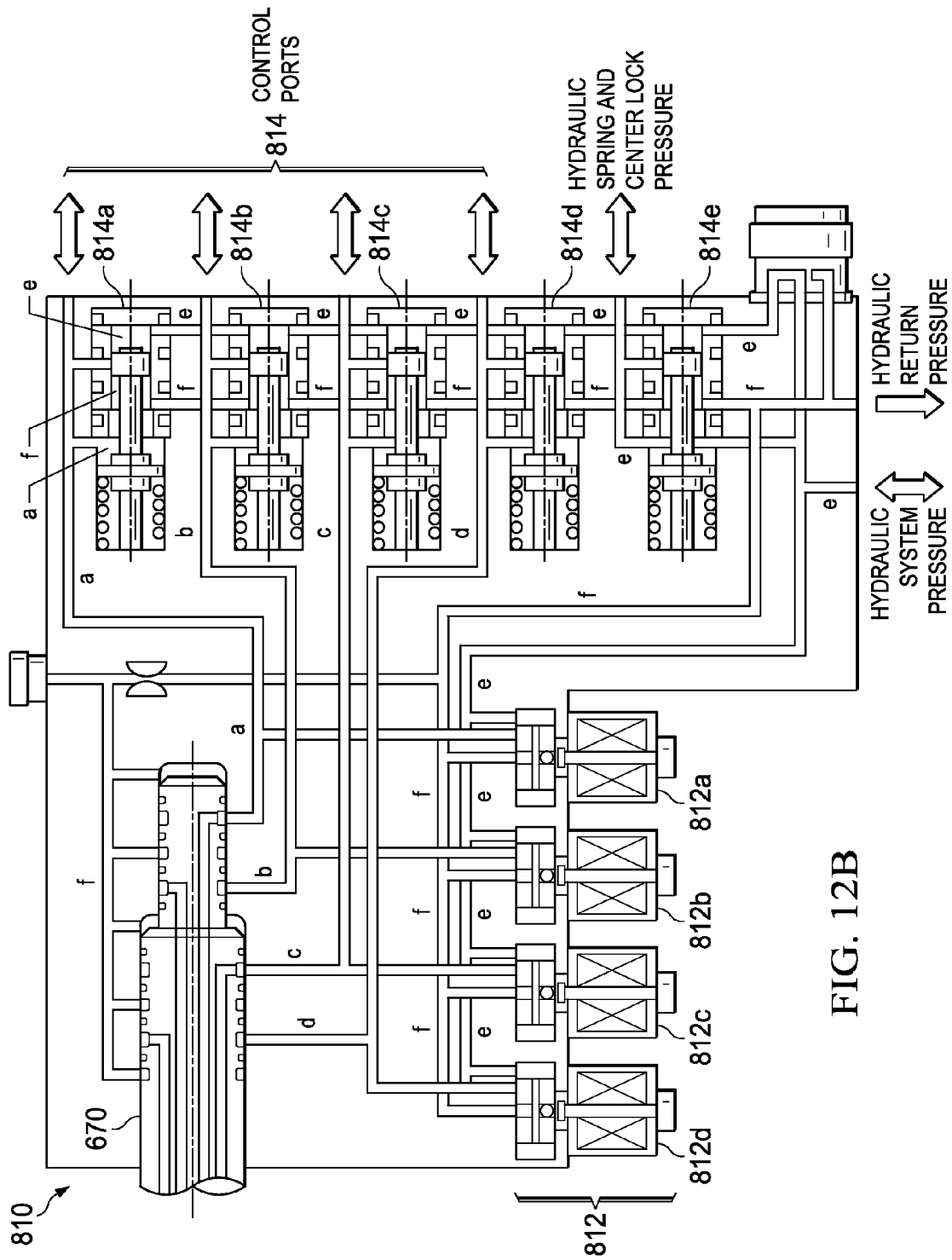
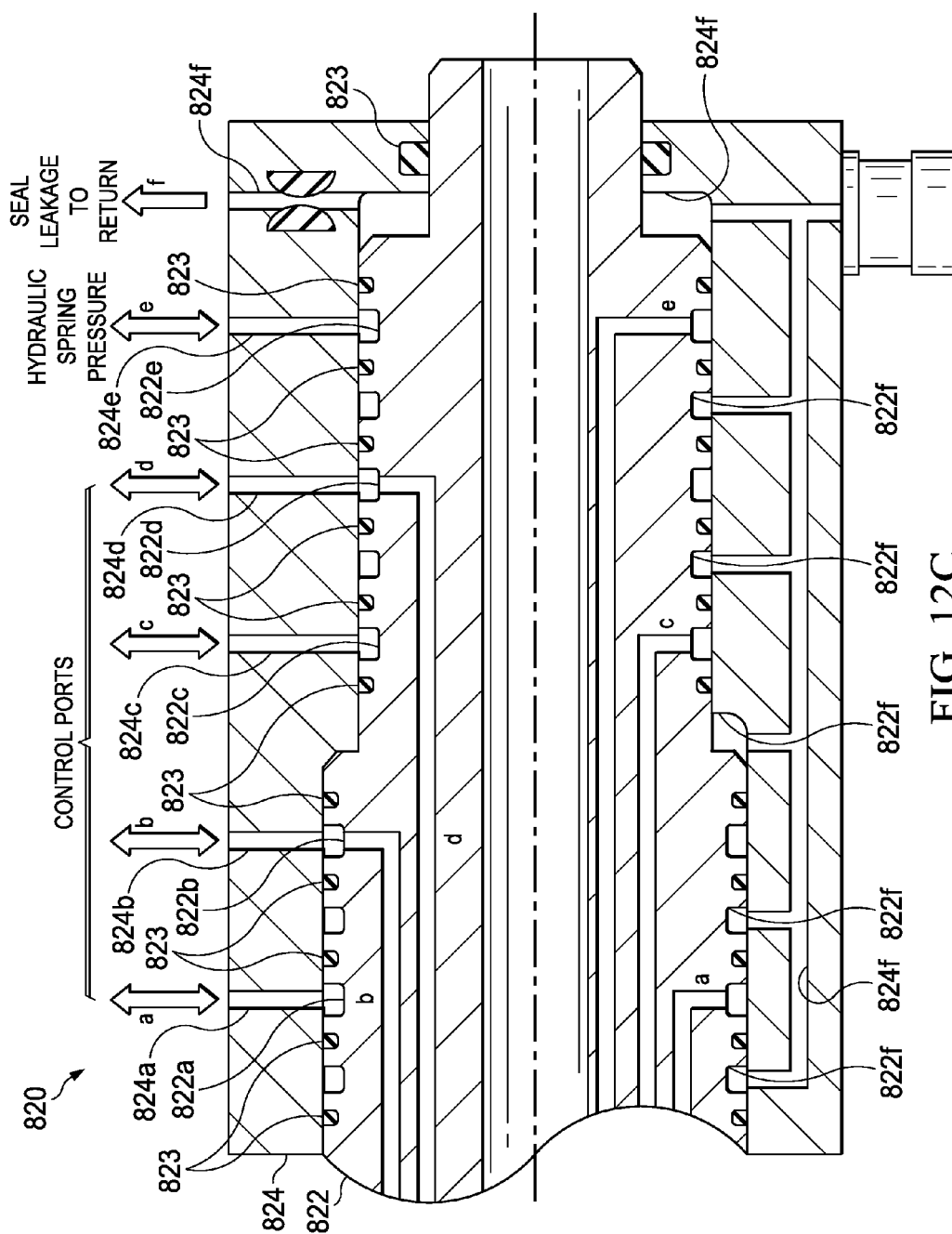


FIG. 12B



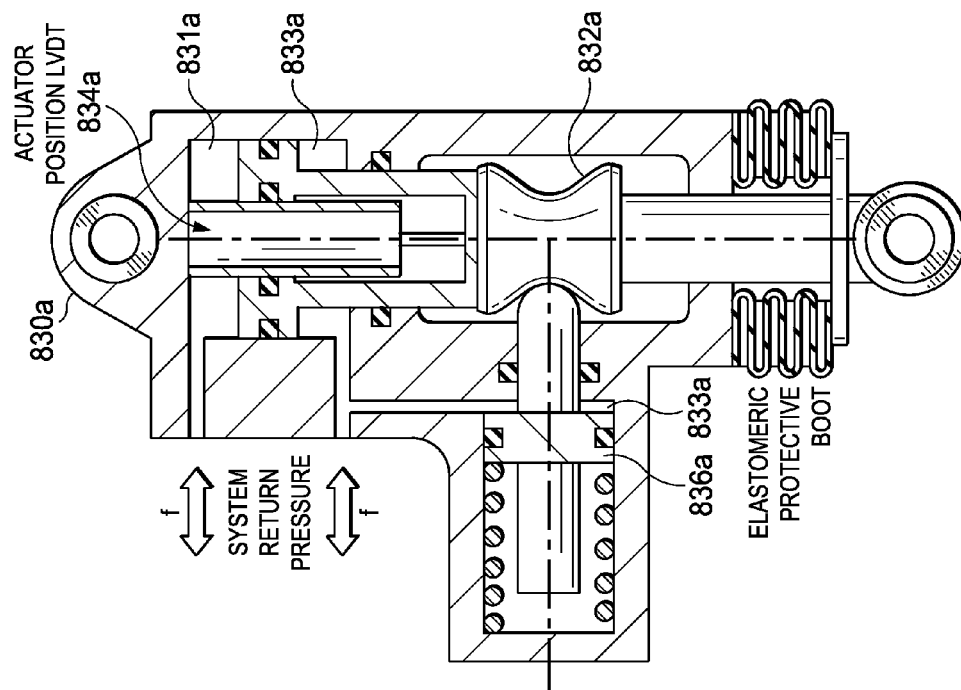


FIG. 12D

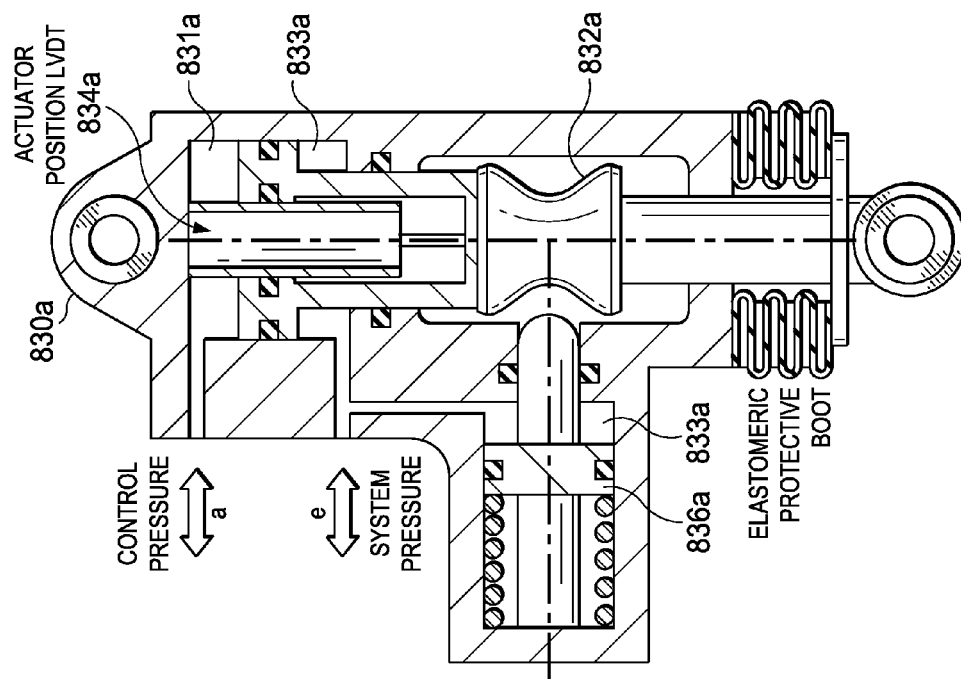
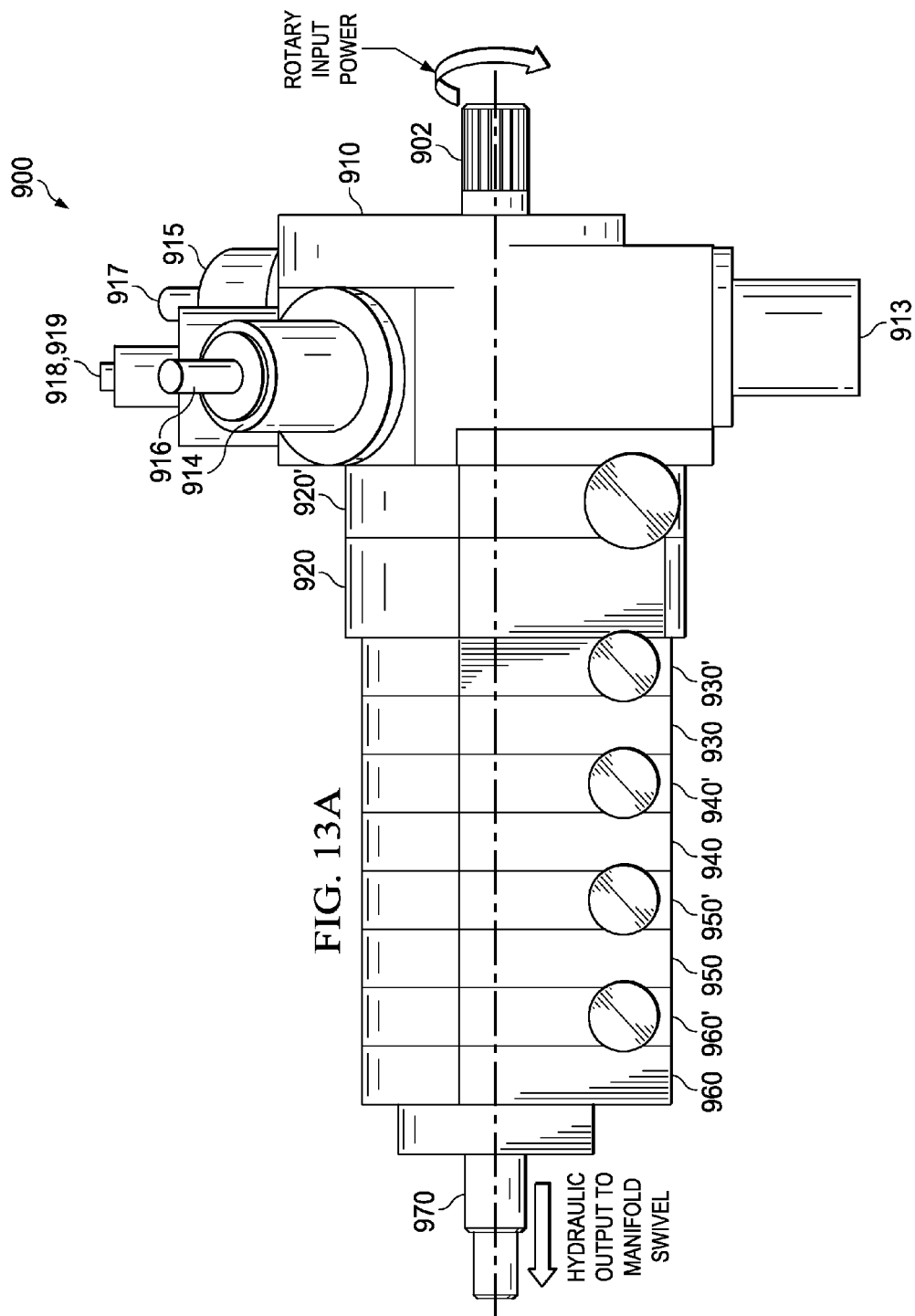


FIG. 12E



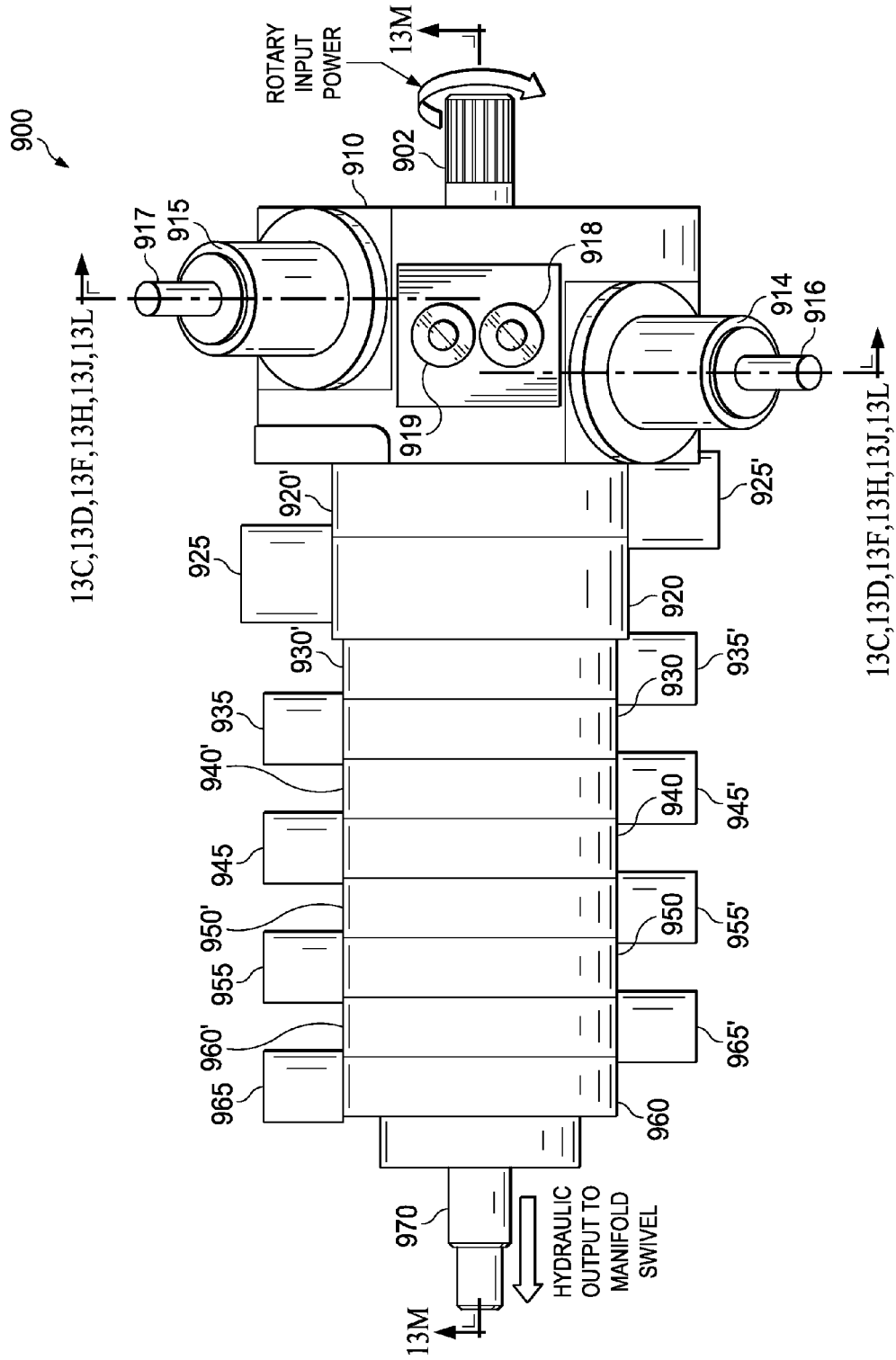


FIG. 13B



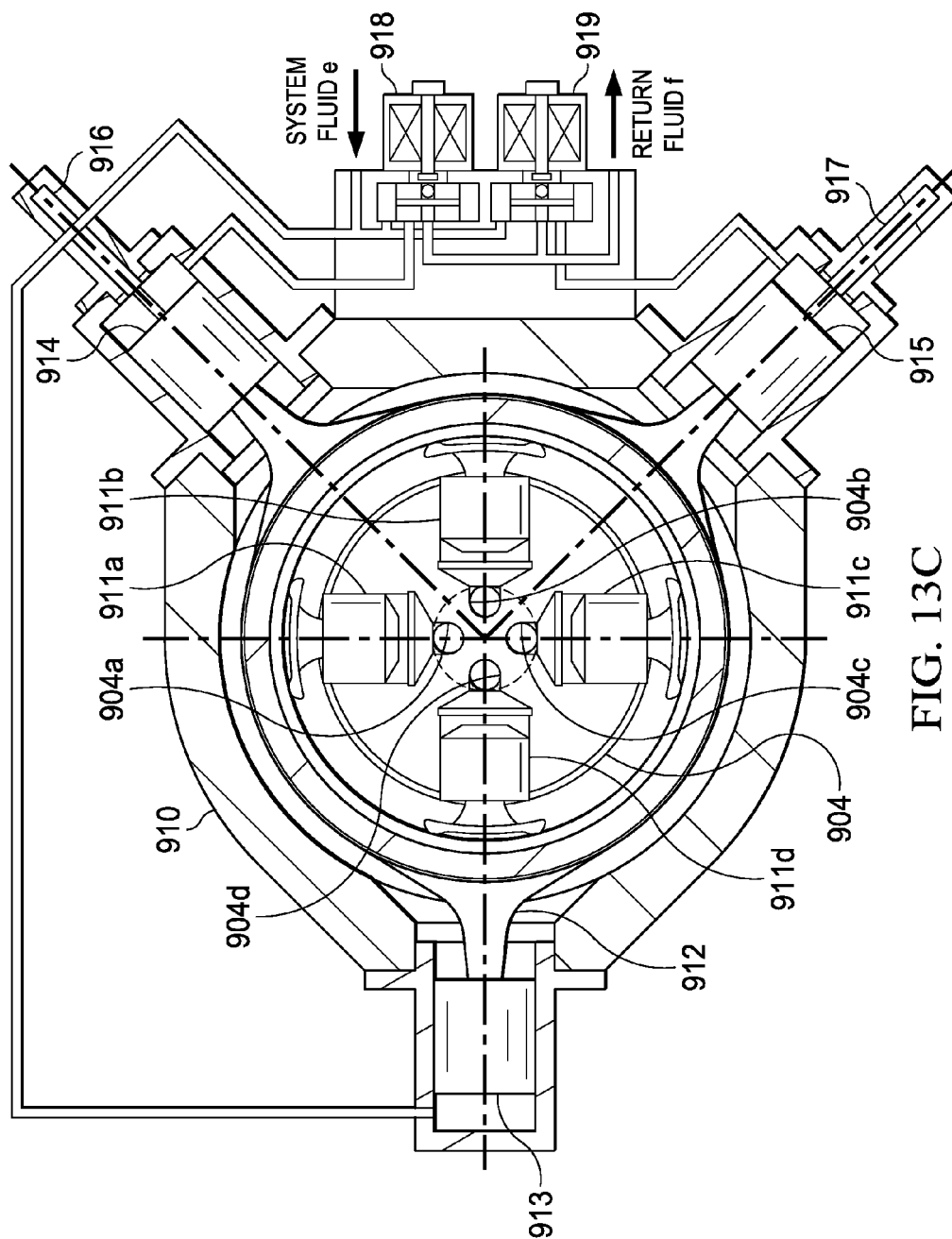
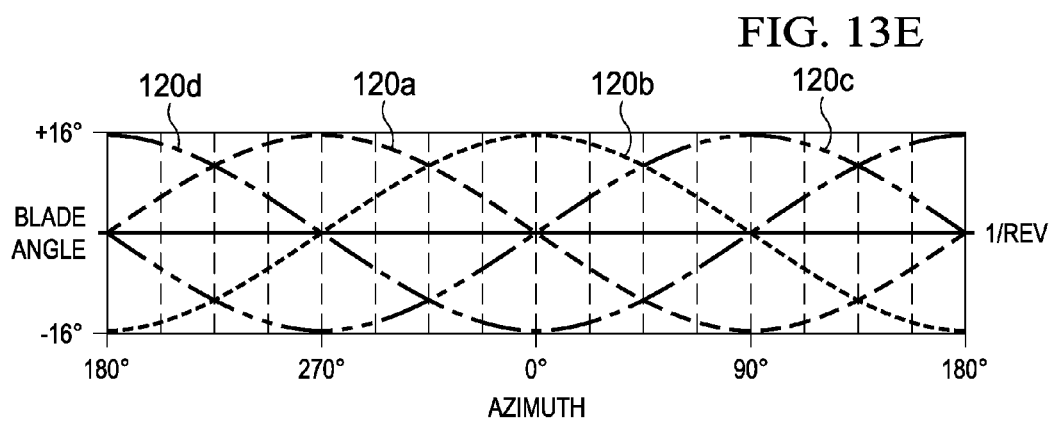
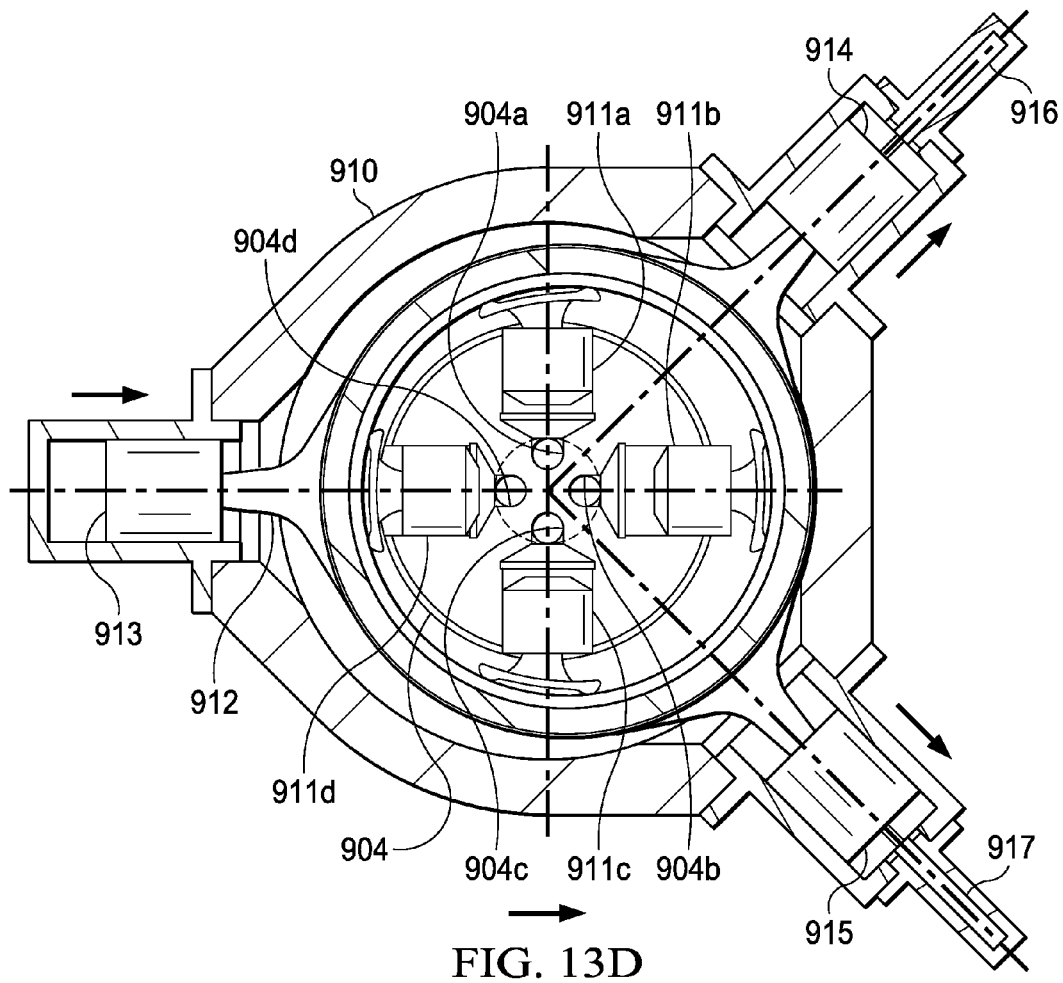
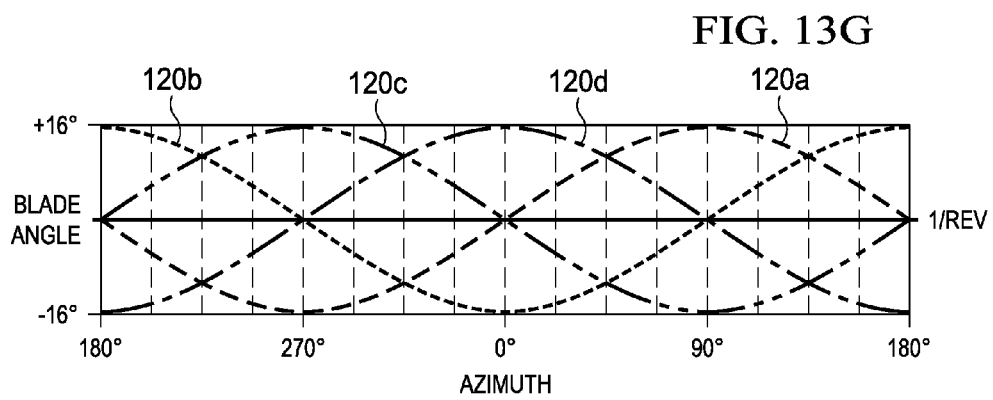
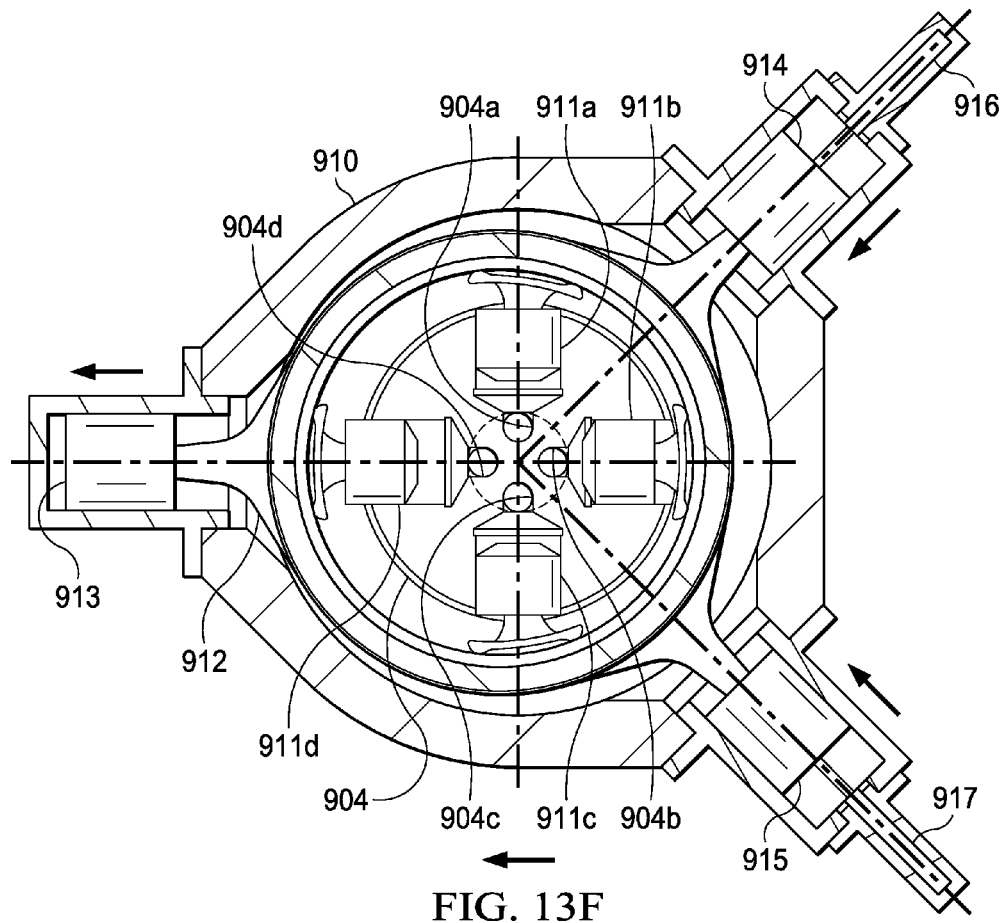


FIG. 13C





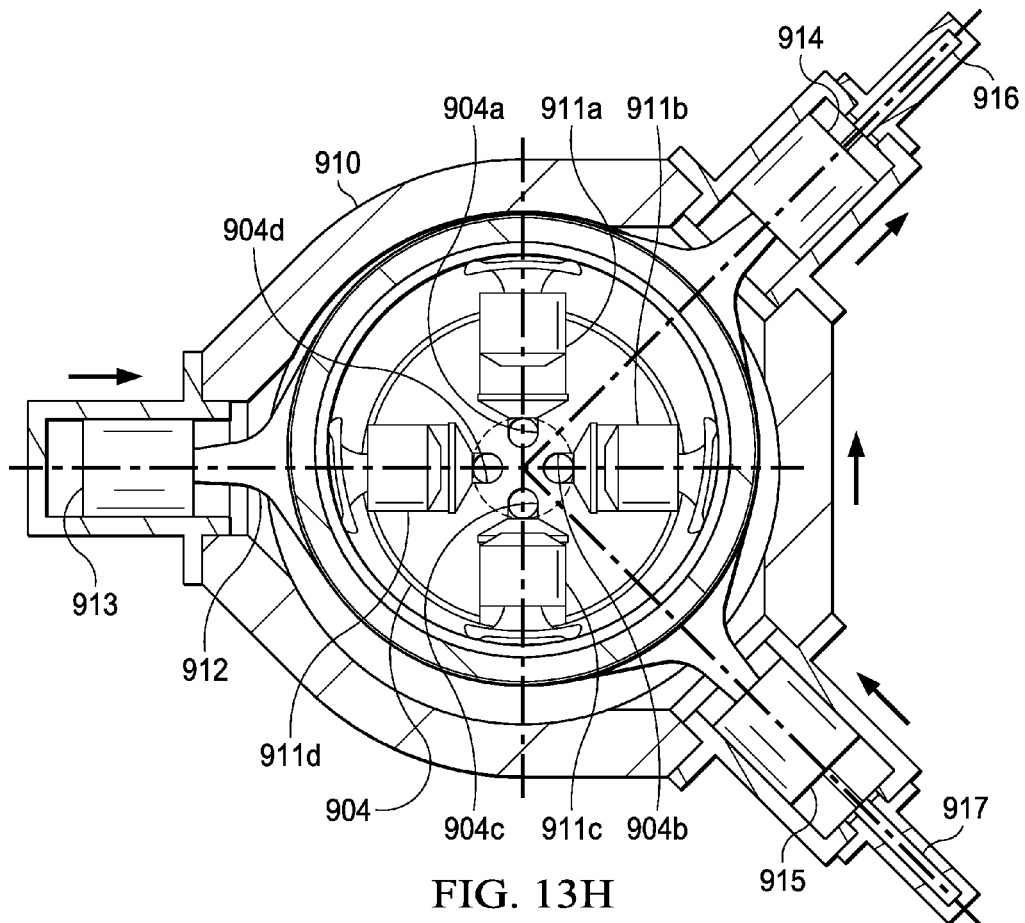
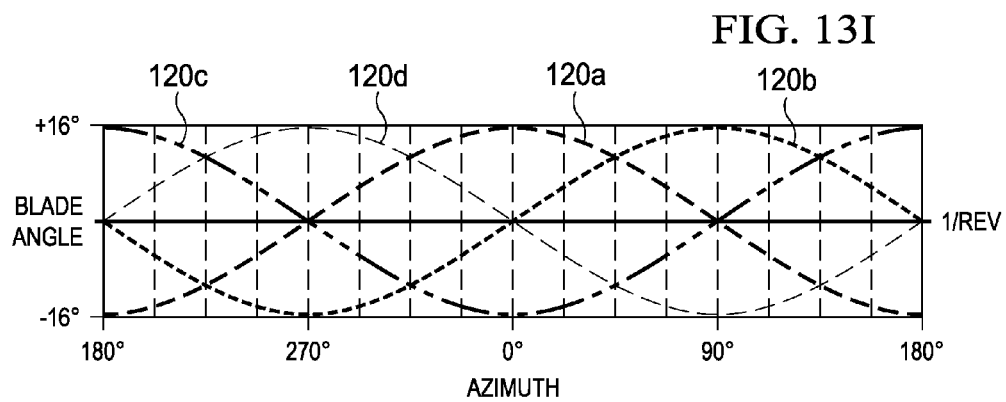
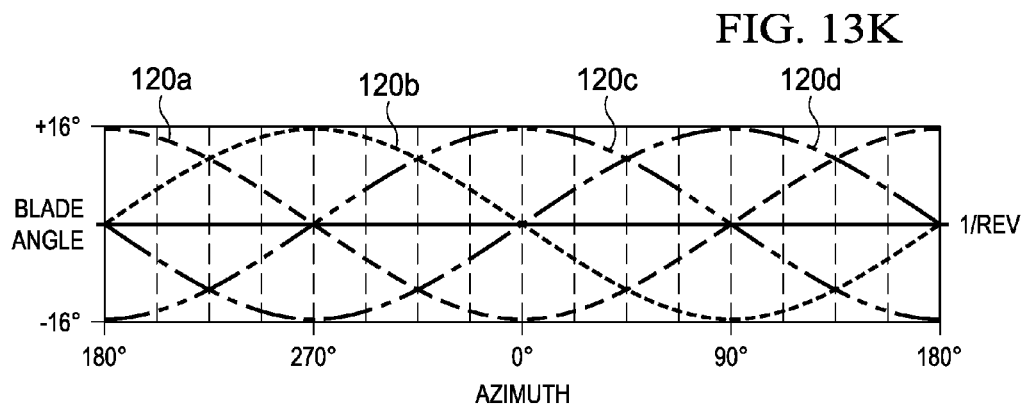
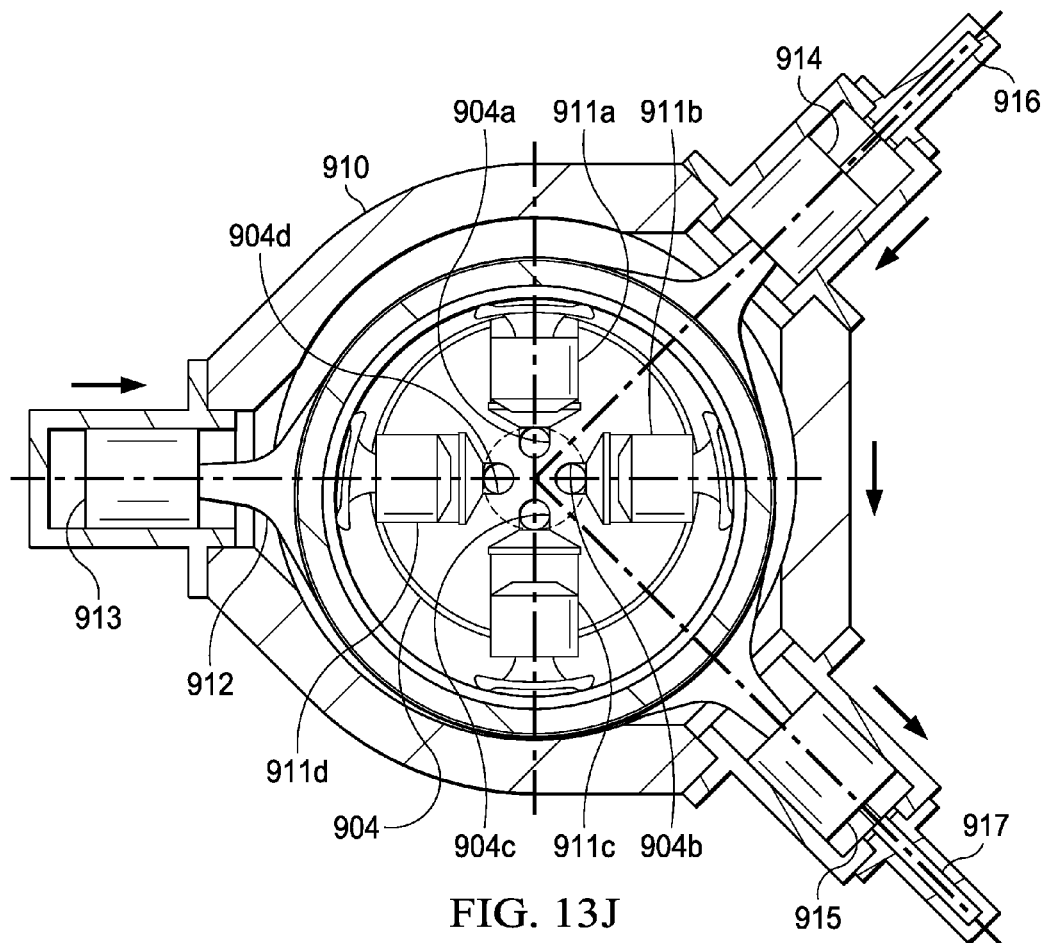


FIG. 13H





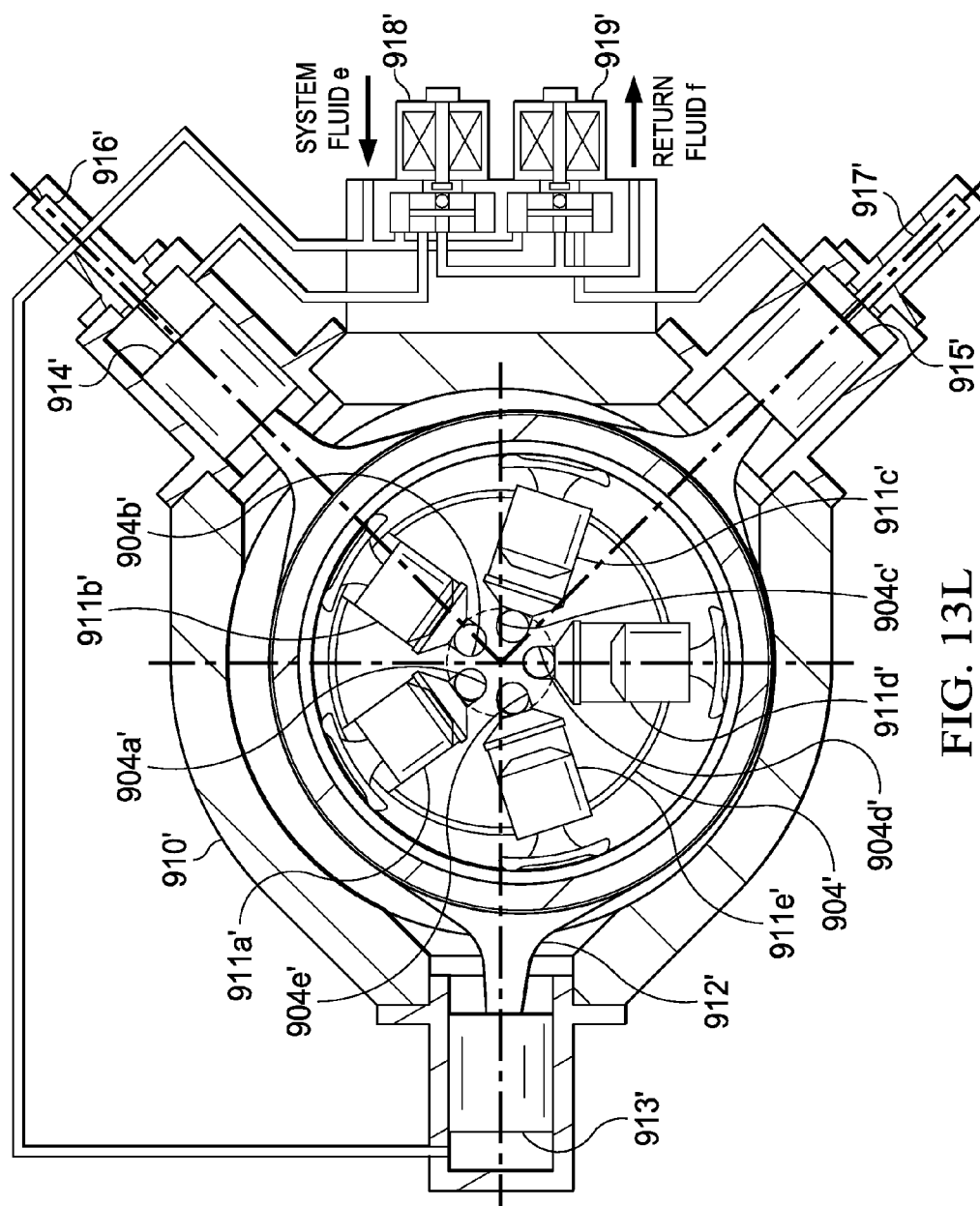
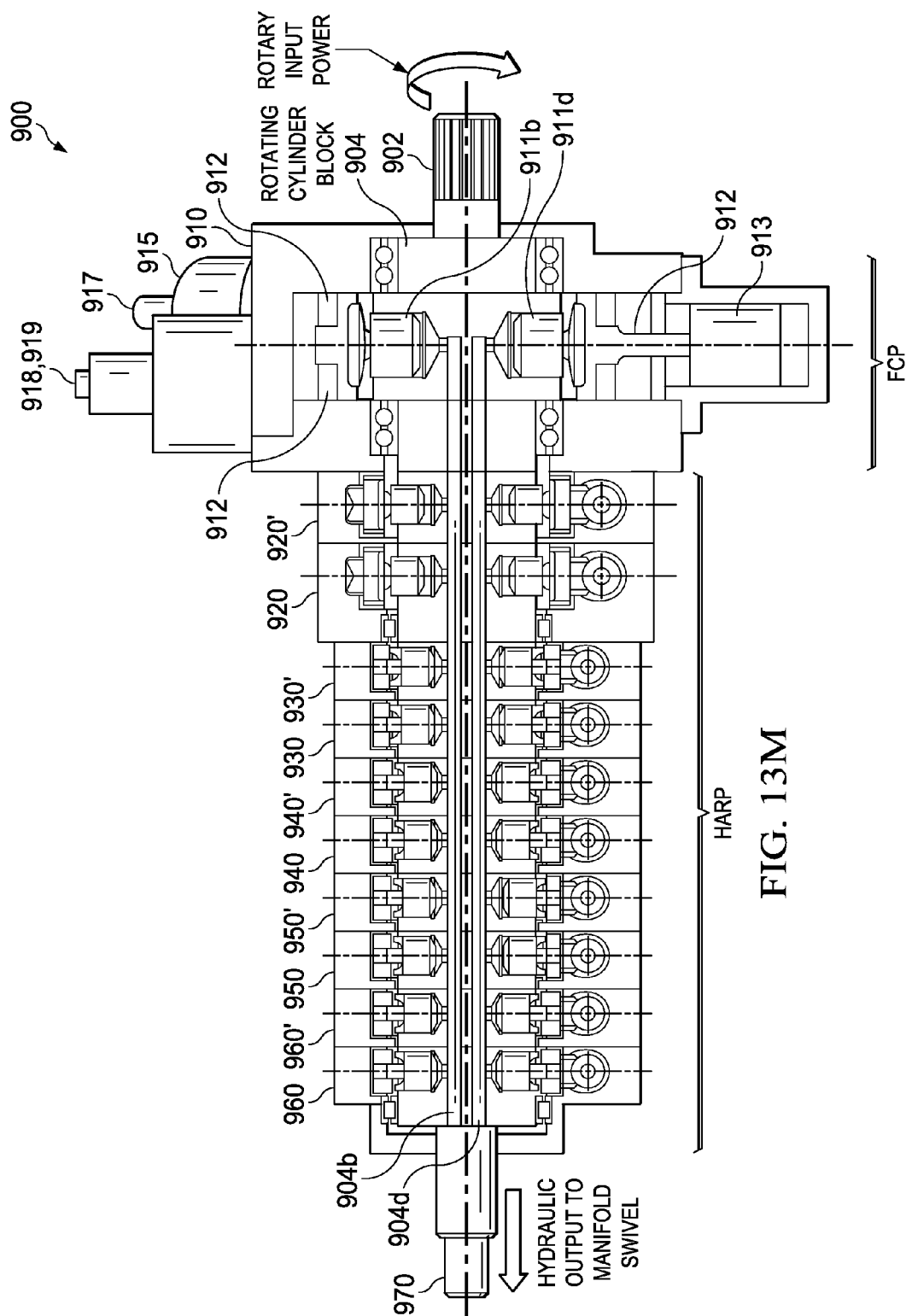
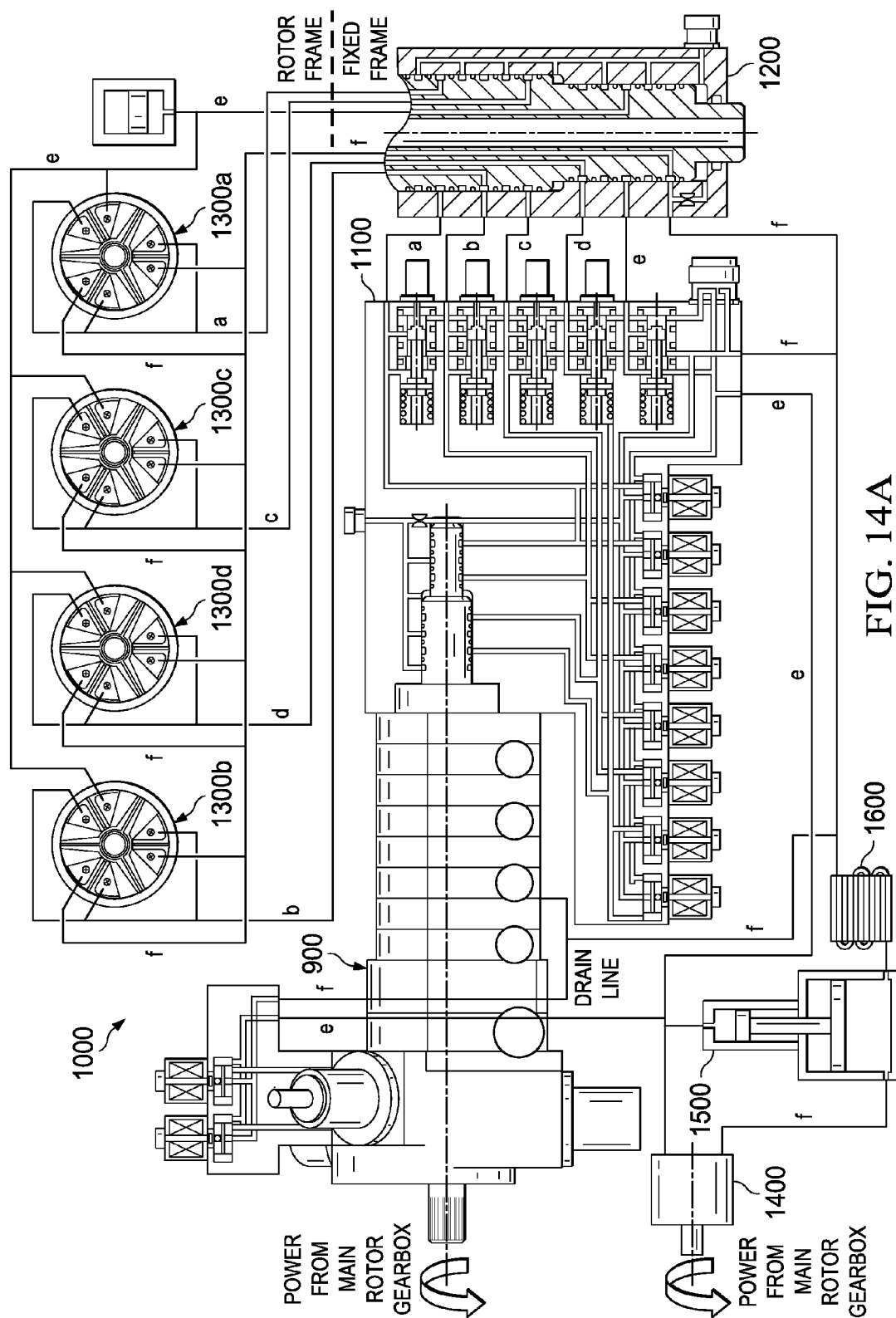


FIG. 13L







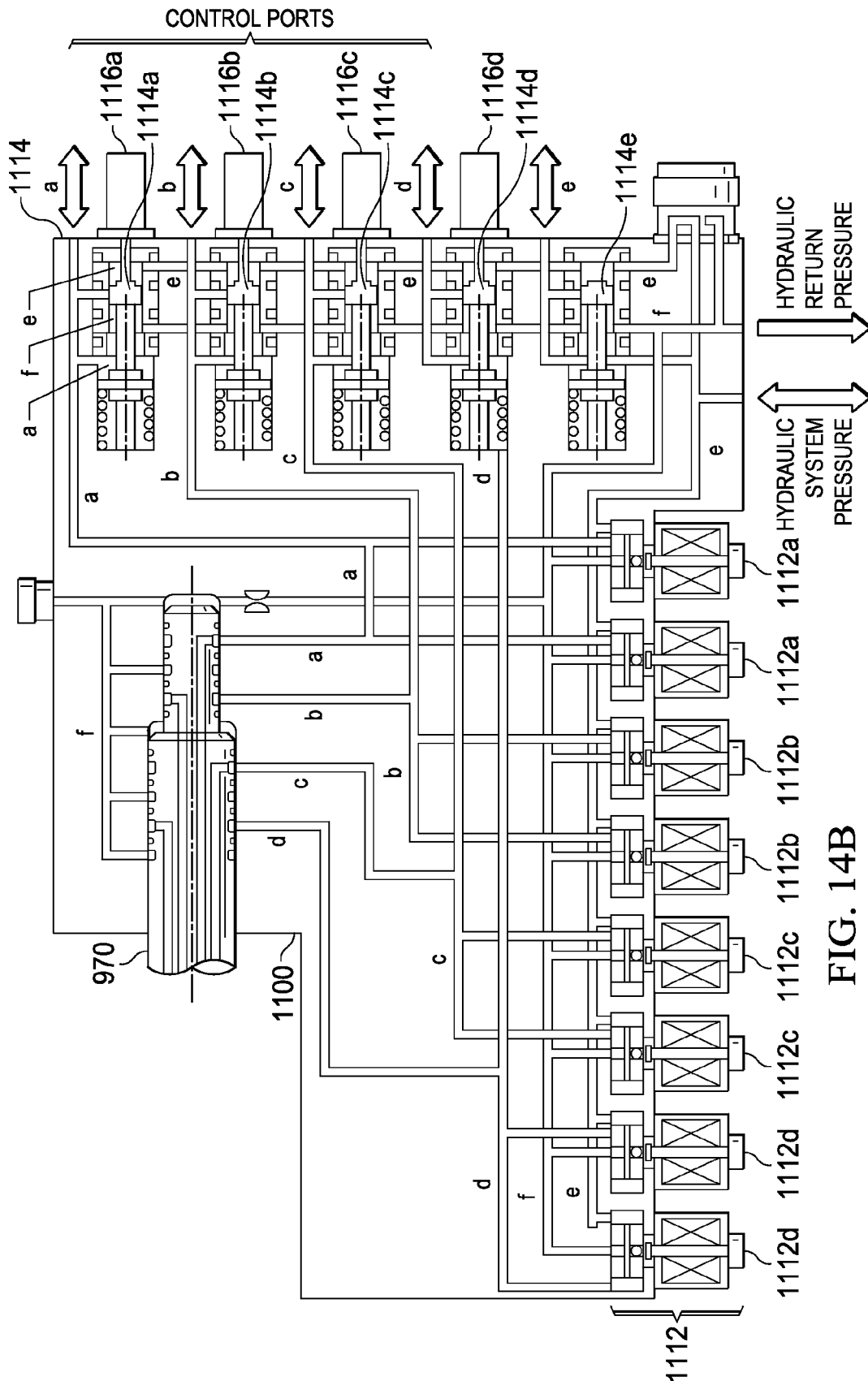


FIG. 14B

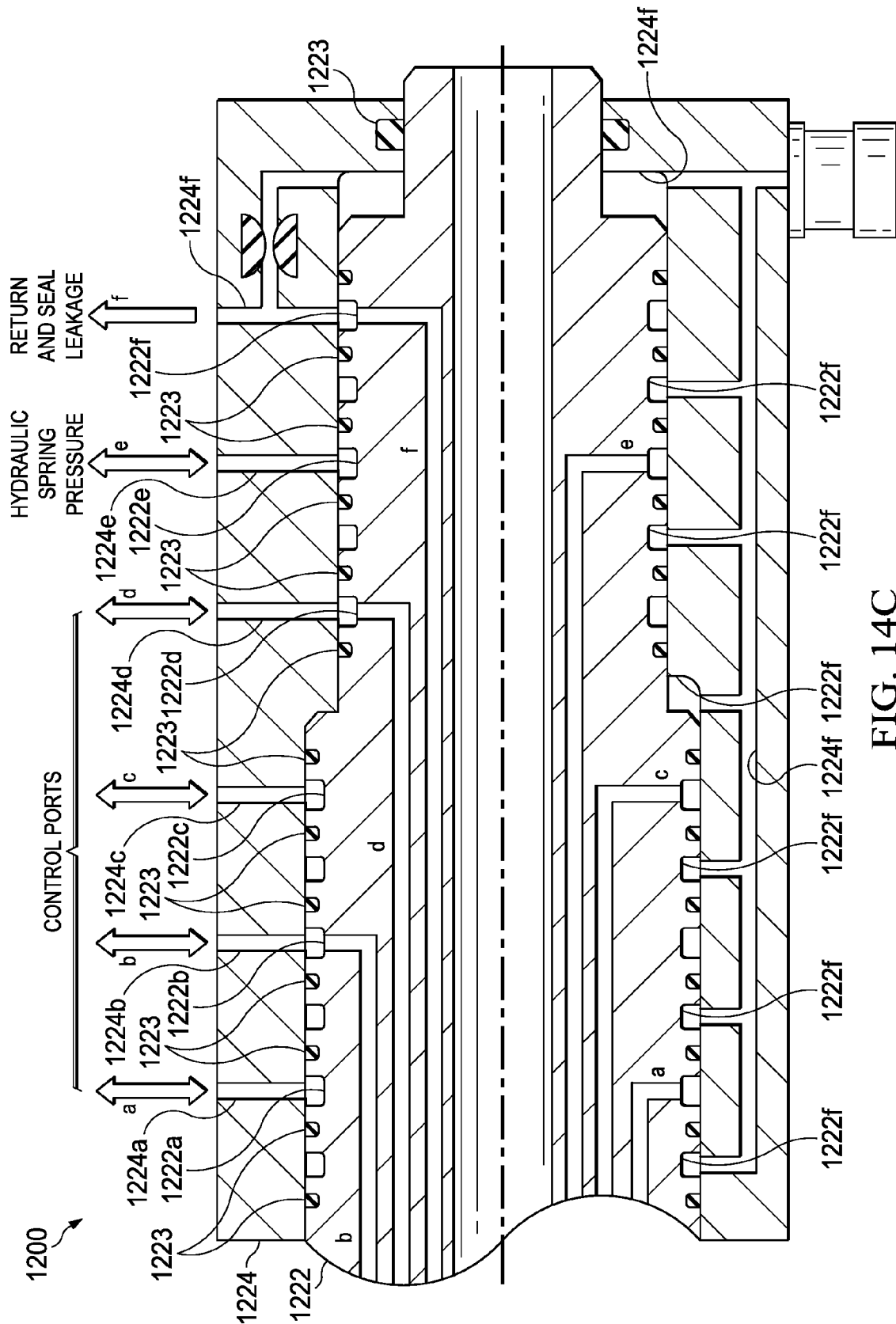


FIG. 14C

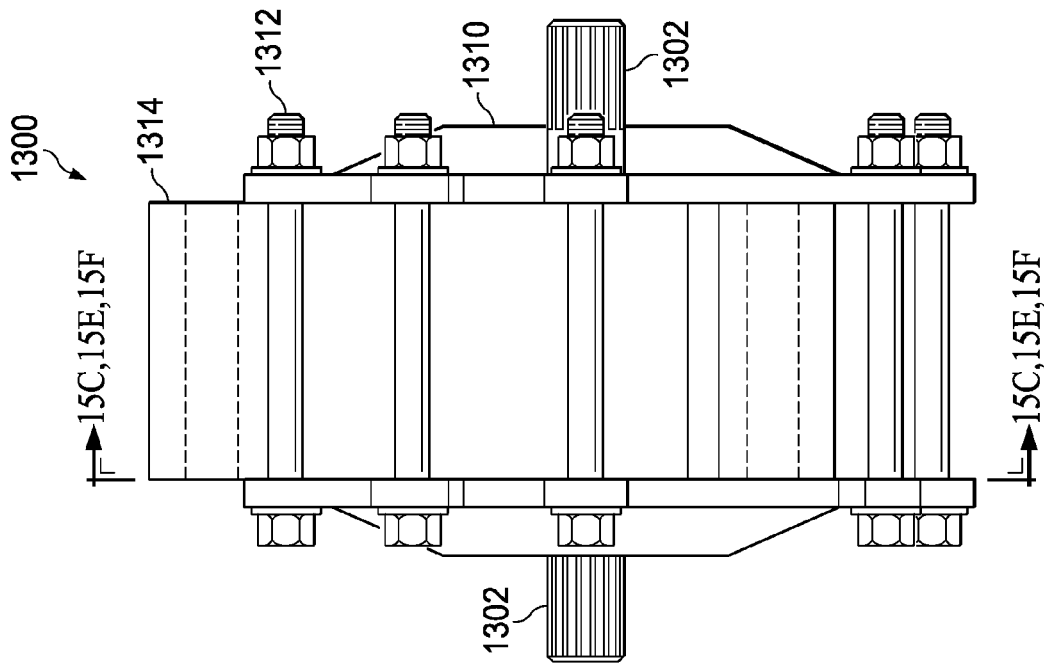


FIG. 15B

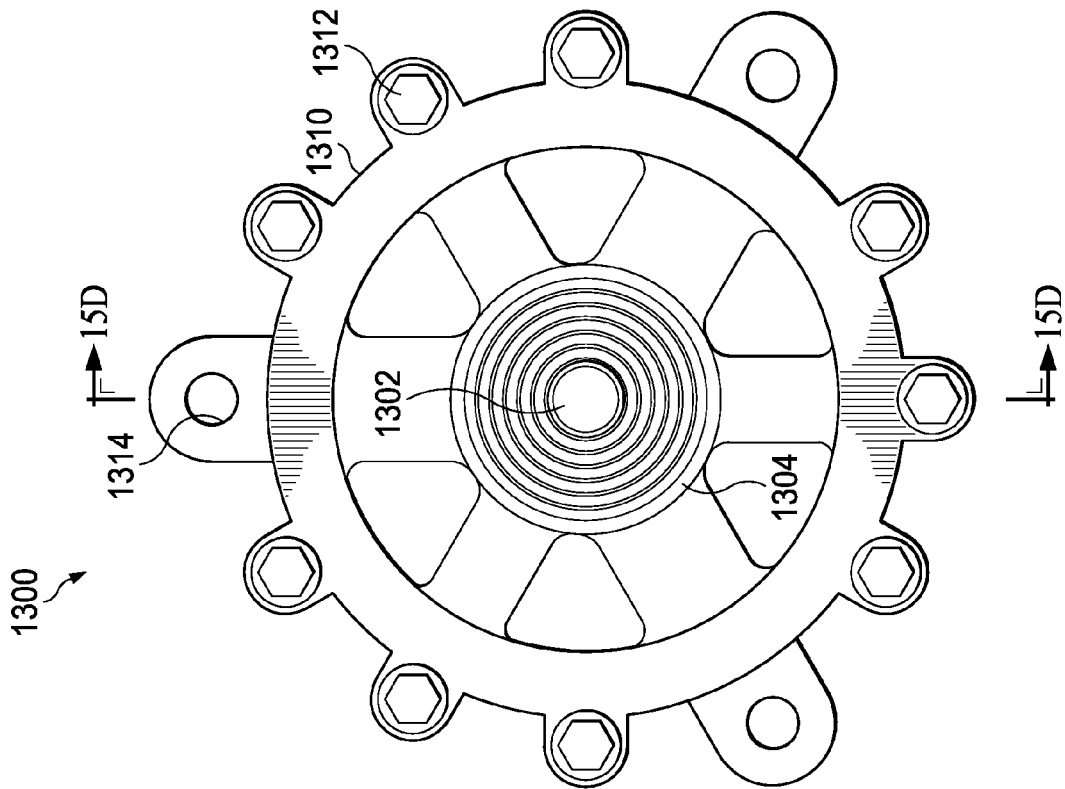


FIG. 15A

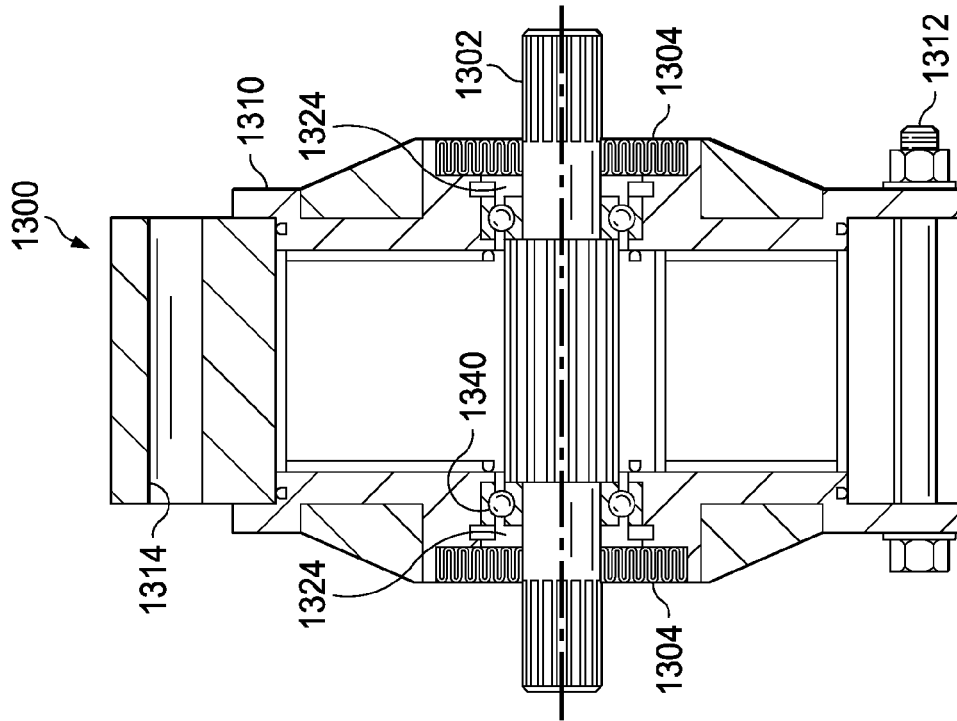


FIG. 15D

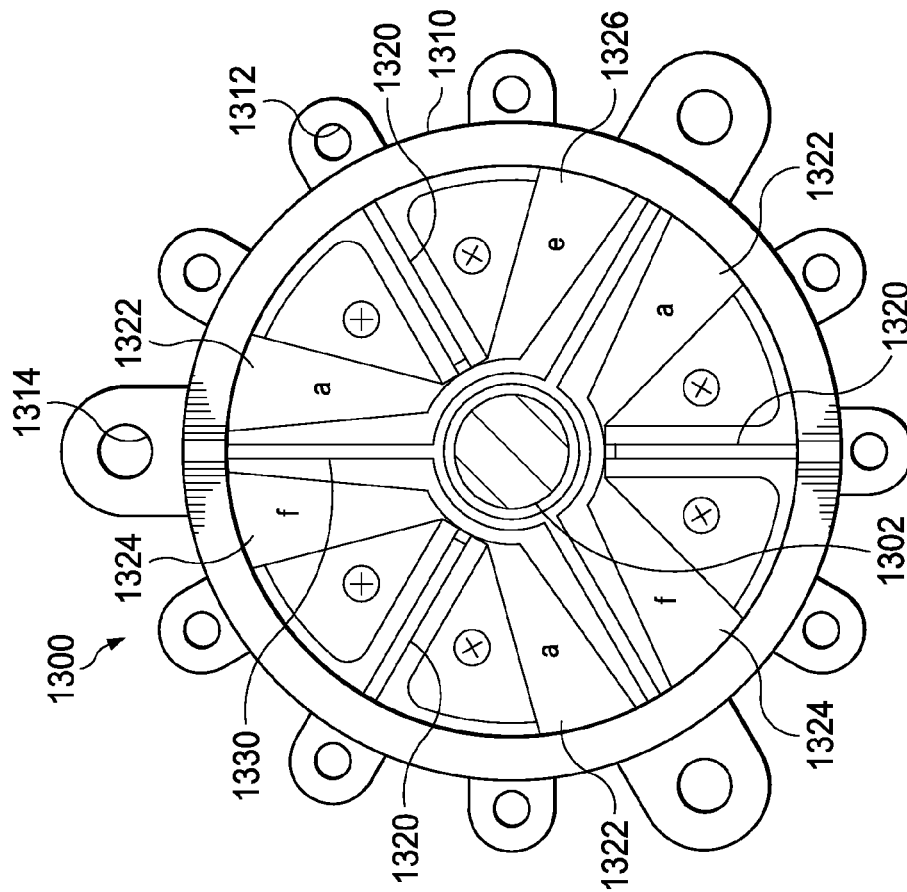


FIG. 15C

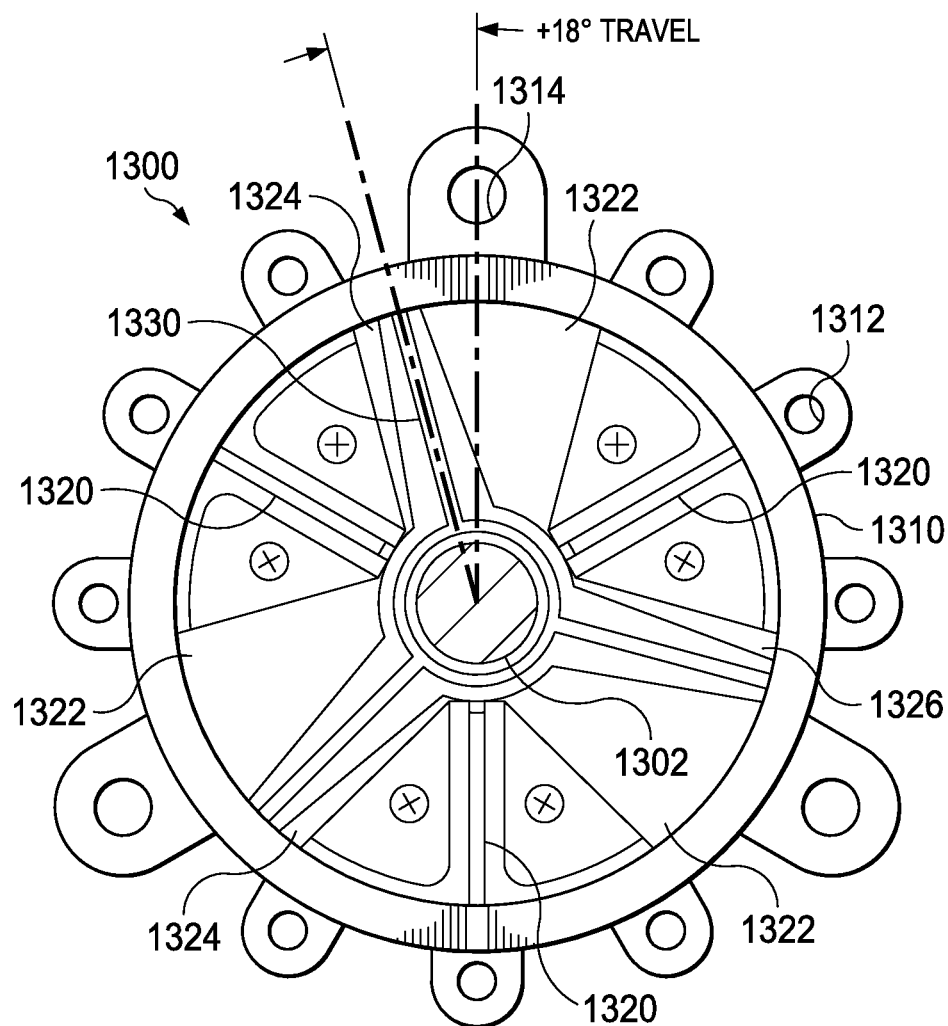


FIG. 15E

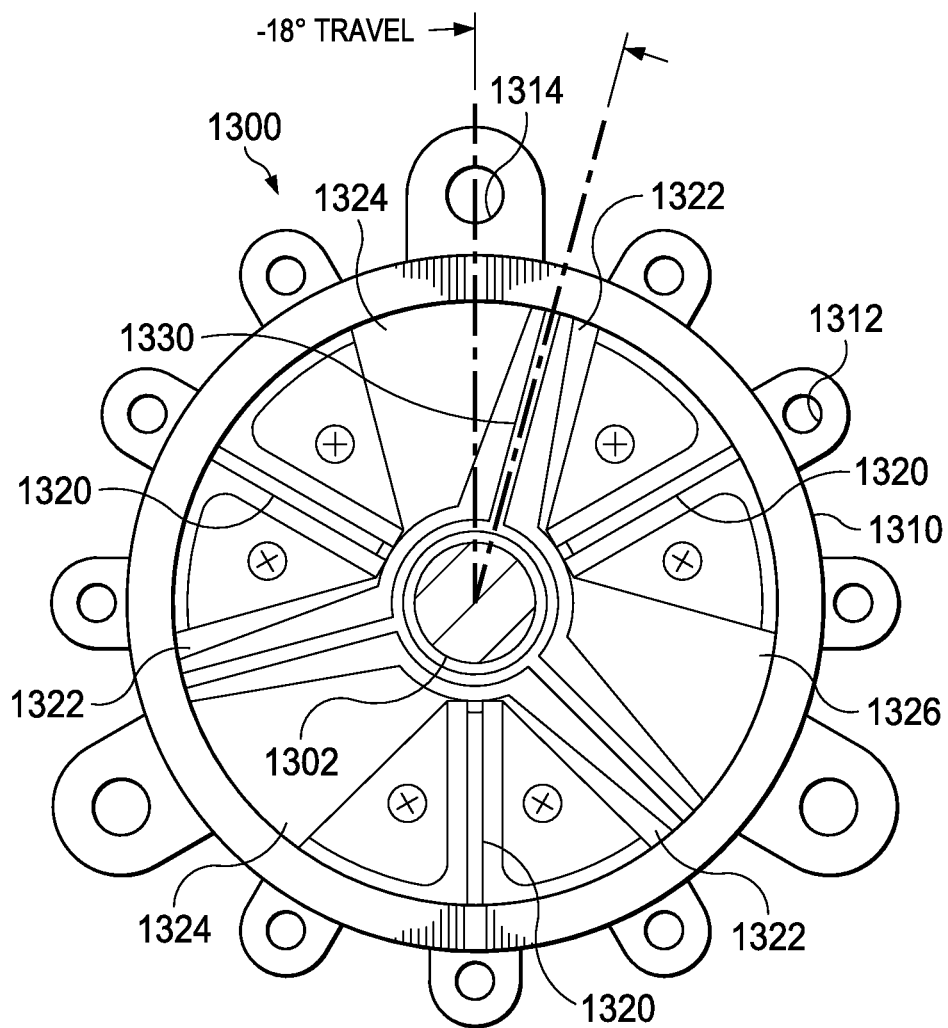


FIG. 15F

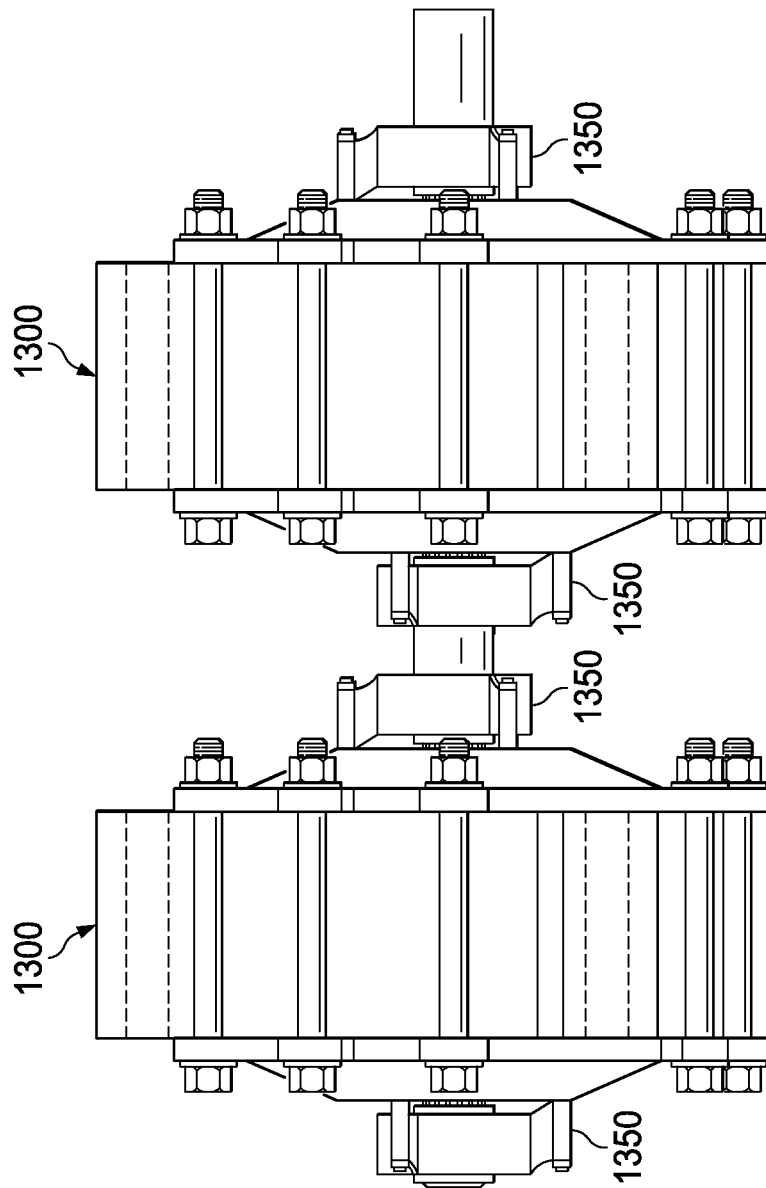


FIG. 16A

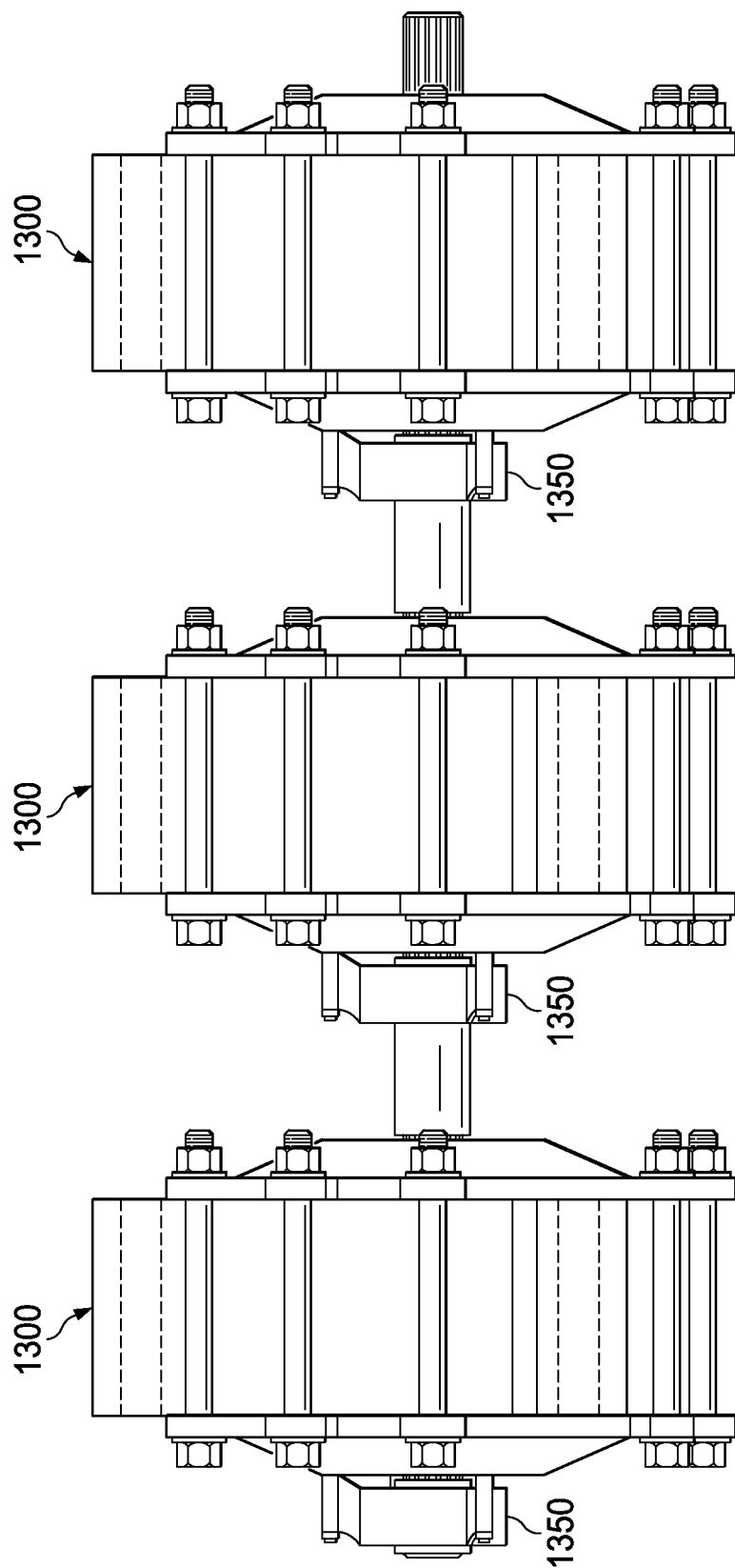


FIG. 16B



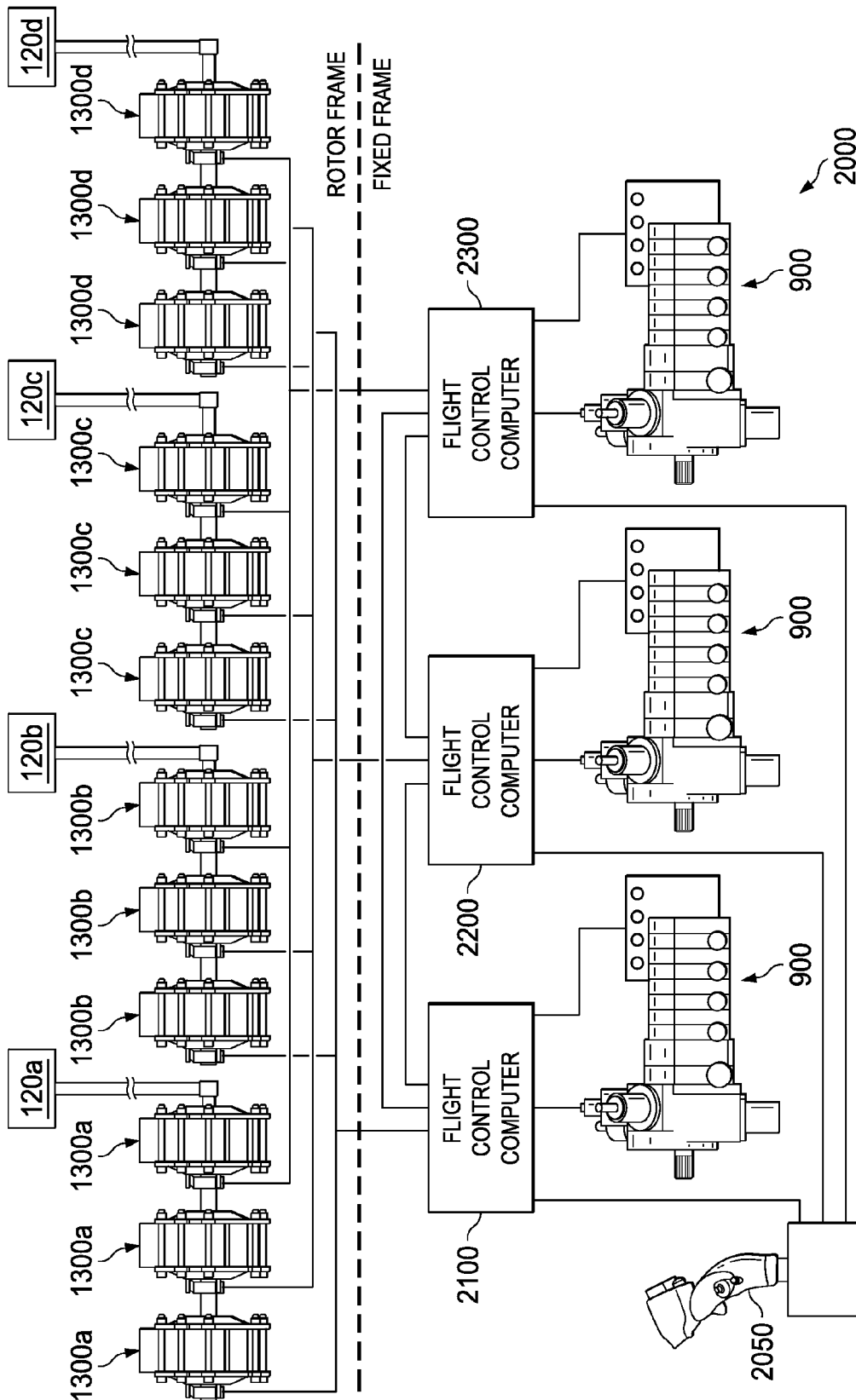


FIG. 17A

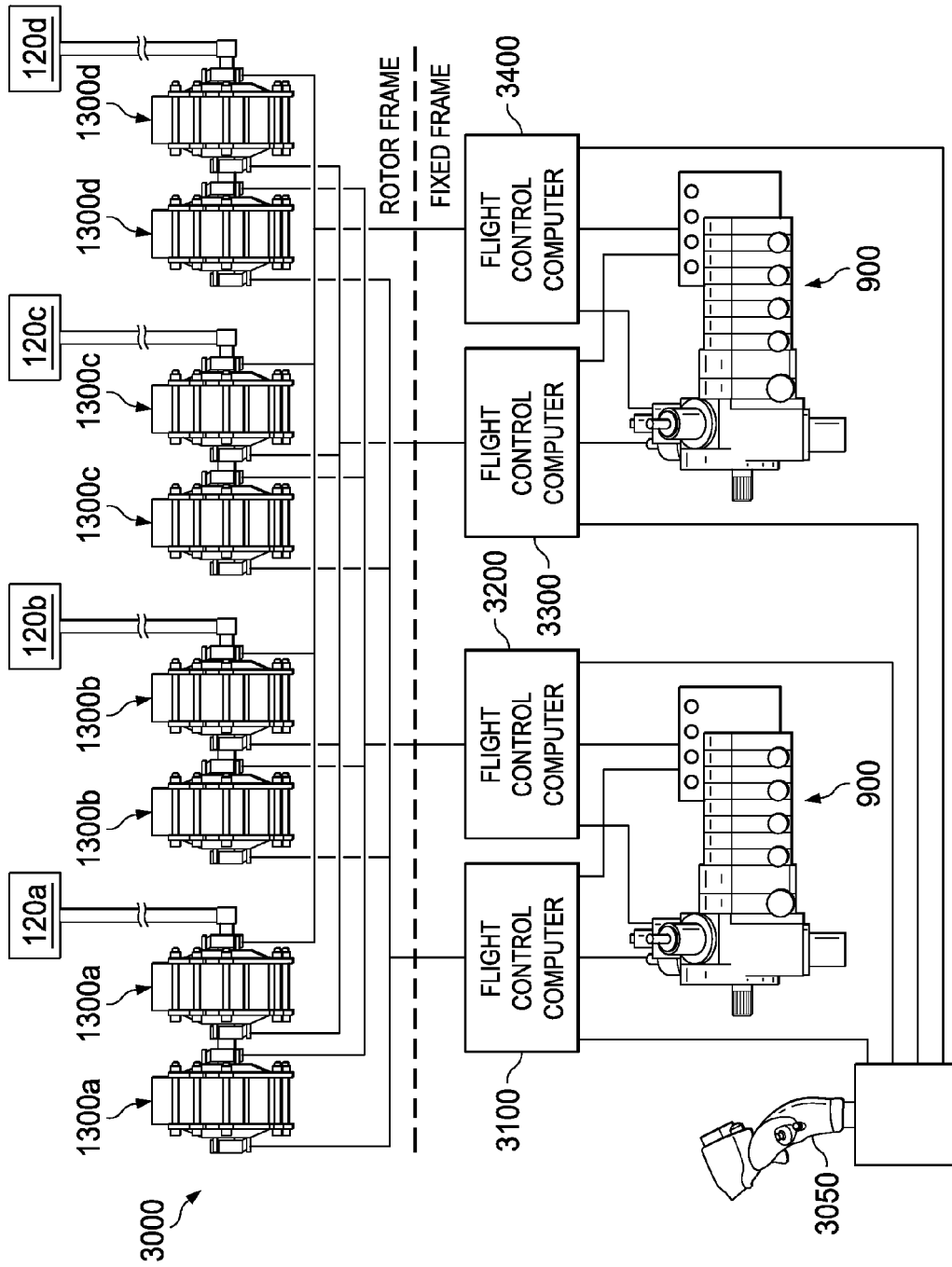


FIG. 17B

1

# INDEPENDENT BLADE CONTROL SYSTEM WITH ROTARY BLADE ACTUATOR

## TECHNICAL FIELD

This invention relates generally to rotorcraft blade control, and more particularly, to an independent blade control system with a rotary blade actuator.

## BACKGROUND

A rotorcraft may include one or more rotor systems. One example of a rotorcraft rotor system is a main rotor system. A main rotor system may generate aerodynamic lift to support the weight of the rotorcraft in flight and thrust to counteract aerodynamic drag and move the rotorcraft in forward flight. Another example of a rotorcraft rotor system is a tail rotor system. A tail rotor system may generate thrust in the same direction as the main rotor system's rotation to counter the torque effect created by the main rotor system. A rotor system may include one or more devices to rotate, deflect, and/or adjust rotor blades.

## SUMMARY

Particular embodiments of the present disclosure may provide one or more technical advantages. A technical advantage of one embodiment may include the capability to implement independent blade control on a rotor system. A technical advantage of one embodiment may include the capability to provide a reliable independent blade control system without the need for redundant electrical or mechanical systems, condition monitoring systems, or secondary load paths. A technical advantage of one embodiment may include the capability to control an independent blade control system mechanically. A technical advantage of one embodiment may include the capability to conserve power in an independent blade control system.

Certain embodiments of the present disclosure may include some, all, or none of the above advantages. One or more other technical advantages may be readily apparent to those skilled in the art from the figures, descriptions, and claims included herein.

## BRIEF DESCRIPTION OF THE DRAWINGS

To provide a more complete understanding of the present invention and the features and advantages thereof, reference is made to the following description taken in conjunction with the accompanying drawings, in which:

FIG. 1 shows a rotorcraft according to one example configuration;

FIG. 2 shows the rotor system and blades 120 of FIG. 1 according to one example configuration;

FIG. 3A shows the motion of the blades of FIG. 1 for a frequency of one oscillation per revolution;

FIG. 3B shows the motion of the blades of FIG. 1 for a frequency of three oscillations per revolution;

FIG. 3C shows the motion of the blades of FIG. 1 for a frequency of five oscillations per revolution;

FIGS. 4A-4D shows the motions of the blades of FIG. 1 for a frequency of four oscillations per revolution;

FIG. 5A shows the motion of the blades of FIG. 1 for a frequency of two oscillations per revolution;

FIG. 5B shows the motion of the blades of FIG. 1 for a frequency of six oscillations per revolution;

2

FIGS. 6A and 6B show an example hydraulic actuation system;

FIGS. 7A and 7B show another example hydraulic actuation;

FIGS. 8A and 8B show yet another example hydraulic actuation system;

FIG. 8C and 8D show an example hydraulic actuation system having two cams;

FIG. 9A shows yet another example hydraulic actuation system according to one embodiment;

FIG. 9B shows the sum of each sinusoidal oscillation pattern generated by the example hydraulic actuation system of FIG. 9A;

FIGS. 10A-10S show a radial fluid device and the frequencies of blade motions produced during operation of the radial fluid device according to one example embodiment;

FIGS. 11A-11K show an alternative embodiment of the radial fluid device of FIGS. 10A-10S and the frequencies of blade motions produced during operation of this alternative embodiment;

FIGS. 12A-12E show an individual blade control (IBC) system featuring the radial fluid device of FIGS. 10A-10S according to one example embodiment;

FIGS. 13A-13K and 13M show a radial fluid device and the frequencies of Blade motions produced during operation of the radial fluid device according to another example embodiment;

FIG. 13L show an alternative embodiment of the radial fluid device of FIGS. 13A-13K and 13M;

FIGS. 14A-14C show an IBC system featuring the radial fluid device of FIGS. 13A-13J and 13M according to one example embodiment;

FIGS. 15A-15F show the blade actuators of the IBC system of FIGS. 14A-14C according to one example embodiment;

FIG. 16A shows two of the blade actuators of FIGS. 15A-15F coupled in series according to one example embodiment;

FIG. 16B shows three of the blade actuators of FIGS. 15A-15F coupled in series according to one example embodiment;

FIG. 17A shows an IBC system featuring three of the radial fluid devices of FIGS. 13A-13J and 13M and four sets of the coupled blade actuators of FIG. 16B according to one example embodiment; and

FIG. 17B shows an IBC system featuring two of the radial fluid devices of FIGS. 13A-13J and 13M and four sets of the coupled blade actuators of FIG. 16A according to one example embodiment.

## DETAILED DESCRIPTION OF THE DRAWINGS

### Rotor Systems

FIG. 1 shows a rotorcraft 100 according to one example configuration. Rotorcraft 100 features a rotor system 110, blades 120, a fuselage 130, a landing gear 140, and an empennage 150. Rotor system 110 may rotate blades 120. Rotor system 110 may include a control system for selectively controlling the pitch of each blade 120 in order to selectively control direction, thrust, and lift of rotorcraft 100. Fuselage 130 represents the body of rotorcraft 100 and may be coupled to rotor system 110 such that rotor system 110 and blades 120 may move fuselage 130 through the air. Landing gear 140 supports rotorcraft 100 when rotorcraft 100 is landing and/or when rotorcraft 100 is at rest on the ground. Empennage 150 represents the tail section of the aircraft and features components of a rotor system 110 and blades 120'. Blades 120' may provide thrust in the same direction as the rotation of blades 120 so as to counter the torque effect created by rotor system

110 and blades 120. Teachings of certain embodiments relating to rotor systems described herein may apply to rotor system 110 and/or other rotor systems, such as other tilt rotor and helicopter rotor systems. It should also be appreciated that teachings from rotorcraft 100 may apply to aircraft other than rotorcraft, such as airplanes and unmanned aircraft, to name a few examples.

FIG. 2 shows rotor system 110 and blades 120 of FIG. 1 according to one example configuration. In the example configuration of FIG. 2, rotor system 110 features a power train 112, a hub 114, a swashplate 116, and pitch links 118. In some examples, rotor system 110 may include more or fewer components. For example, FIG. 2 does not show components such as a gearbox, a swash plate, drive links, drive levers, and other components that may be incorporated.

Power train 112 features a power source 112a and a drive shaft 112b. Power source 112a, drive shaft 112b, and hub 114 are mechanical components for transmitting torque and/or rotation. Power train 112 may include a variety of components, including an engine, a transmission, and differentials. In operation, drive shaft 112b receives torque or rotational energy from power source 112a and rotates hub 114. Rotation of rotor hub 114 causes blades 120 to rotate about drive shaft 112b.

Swashplate 116 translates rotorcraft flight control input into motion of blades 120. Because blades 120 are typically spinning when the rotorcraft is in flight, swashplate 116 may transmit flight control input from the non-rotating fuselage to the hub 114, blades 120, and/or components coupling hub 114 to blades 120 (e.g., grips and pitch horns). References in this description to coupling between a pitch link and a hub may also include, but are not limited to, coupling between a pitch link and a blade or components coupling a hub to a blade.

In some examples, swashplate 116 may include a non-rotating swashplate ring 116a and a rotating swashplate ring 116b. Non-rotating swashplate ring 116a does not rotate with drive shaft 112b, whereas rotating swashplate ring 116b does rotate with drive shaft 112b. In the example of FIG. 2, pitch links 118 connect rotating swashplate ring 116b to blades 120.

In operation, according to one example embodiment, translating the non-rotating swashplate ring 116a along the axis of drive shaft 112b causes the pitch links 118 to move up or down. This changes the pitch angle of all blades 120 equally, increasing or decreasing the thrust of the rotor and causing the aircraft to ascend or descend. Tilting the non-rotating swashplate ring 116a causes the rotating swashplate 116b to tilt, moving the pitch links 118 up and down cyclically as they rotate with the drive shaft. This tilts the thrust vector of the rotor, causing rotorcraft 100 to translate horizontally following the direction the swashplate is tilted.

#### Independent Blade Control

Independent blade control (IBC) may refer to the ability to control motion of individual rotor system blades, such as blades 120a-120d. For example, IBC may provide the ability to control harmonic motions of individual blades as the individual blades rotate. For discussion purposes, harmonic blade motions may be separated into three categories: harmonic cyclic motions, harmonic collective motions, and reactionless motions. These three categories do not define any particular mechanization to drive the blades. Rather, these categories may be defined by the characteristics of their oscillatory blade motions.

Harmonic cyclic motions may represent rotor blade sinusoidal motions similar to those that can be generated by application of oscillatory swashplate tilting inputs to the non-

rotating half of the swashplate. In the example of FIG. 2, harmonic cyclic motions may be similar to the application of tilting inputs to non-rotating swashplate ring 116a.

The frequency of harmonic cyclic motions may be expressed as specific multiple integers of rotor revolution frequency (e.g., revolutions per minute, or RPM). On a four-bladed rotor system such as rotor system 110, the frequencies of harmonic cyclic oscillations are odd integer values (e.g., one blade oscillation per revolution, 3/rev, 5/rev, 7/rev, etc.).

FIGS. 3A-3C show the motions of blades 120a-120d for frequencies of one, three, and five blade oscillations per revolution. FIG. 3A shows the motion of blades 120a-120d for a frequency of one oscillation per revolution. One blade oscillation per revolution may be accomplished, for example, by maintaining non-rotating swashplate ring 116a in a fixed, tilted position. FIG. 3B shows the motion of blades 120a-120d for a frequency of three oscillations per revolution. FIG. 3C shows the motion of blades 120a-120d for a frequency of five oscillations per revolution.

Harmonic collective motions move all blades sinusoidally in phase with each other. In the example of FIG. 2, harmonic collective motions may be similar to the application of axial inputs to non-rotating swashplate ring 116a.

The frequency of harmonic collective motions may be expressed as specific multiple integers of rotor revolution frequency (e.g., RPM). In particular, the frequency of harmonic collective motions may be expressed as multiples of the number of blades on the rotor. On a four-bladed rotor system such as rotor system 110, the frequencies of harmonic collective oscillations are 4/rev, 8/rev, etc. FIGS. 4A-4D shows the motions of blades 120a-120d for a frequency of 4/rev. As shown in FIGS. 4A-4D, blades 120a-120d move uniformly sinusoidally in phase with each other.

Unlike harmonic cyclic and collective motions, reactionless motions cannot be replicated by or analogized to swashplate motions. For a four-bladed rotor system, the frequencies of reactionless motions are 2/rev and 6/rev, which cannot be achieved using the rotor system 110 of FIG. 2. Oscillation frequencies of 2/rev and 6/rev for a four-bladed rotor system results in adjacent blades having a 180 degree phase lag and opposite blades being in phase with each other. FIG. 5A shows the motions of blades 120a-120d for a frequency of 2/rev, and FIG. 5B shows the motions of blades 120a-120d for a frequency of 6/rev. Teachings of certain embodiments recognize that implementing reactionless controls may increase rotor system efficiency as well as reduce noise and vibration.

Thus, IBC may represent the ability to move rotor blades unconstrained from the cyclic and collective kinematic motion limitations imposed by conventional swashplate controls. Although IBC is not a prerequisite to implement cyclic and collective controls, it is a prerequisite to implement reactionless controls.

Teachings of certain embodiments recognize the ability to implement IBC on a rotor system. For discussion purposes, IBC systems may be separated into two categories: partial authority and full authority. Partial-authority IBC systems sum their higher harmonic and reactionless control motions with a swashplate providing fundamental blade motion for cyclic and collective control. Full-authority IBC systems provide for independent blade control through the full range of cyclic and collective motion. In some circumstances, partial-authority IBC systems may be preferable because the total summed amplitudes of higher harmonic and reactionless motions are typically a relatively small percentage of the total blade travel required for cyclic and collective control. Therefore, the failure mode effects of partial-authority IBC actuators are not as critical as with full-authority systems, allowing

for lesser levels of reliability and redundancy. Full-authority IBC systems, on the other hand, may be preferable because they can allow for the elimination of the swashplate and thus elimination of certain drag and weight penalties.

#### Hydraulic Systems

Teachings of certain embodiments recognize the ability to implement IBC by hydraulically actuating the position of each rotor blade. FIGS. 6A and 6B show an example hydraulic actuation system 200. Hydraulic actuation system 200 features a pump 210, control valves 220 (e.g., electro-hydraulic valves), an actuator 230, and a reservoir 240. In operation, pump 210 provides hydraulic fluid to control valves 220, which either provides into or releases fluid out of actuator 230. Changing the volume of fluid in actuator 230 allows hydraulic actuation system 200 to either raise or lower load 250. Control valves 220 may pass hydraulic fluid to reservoir 240, which may provide hydraulic fluid to pump 210, as needed.

In the example of FIGS. 6A and 6B, hydraulic actuation system 200 is a constant-pressure system in that pump 210 provides a constant pressure of hydraulic fluid. In a constant-pressure hydraulic system, the power expended to move the actuator is independent of the applied load on the actuator because power is a function of product flow and system pressure.

Maximum actuator rate capacity is achieved when control valves 220 are commanded to their maximum orifice size, which is also the maximum operating efficiency condition of hydraulic actuation system 200. Thus, the maximum operating efficiency condition occurs when load 250 is largest, as shown in FIG. 6A.

When less than maximum actuator rate is required (such as when load 250' is smaller, as shown in FIG. 6B), control valves 220 throttle down flow by reducing the orifice size and converting the unused power into waste heat. Power is converted to even more waste heat when commanding control valves 220 to move actuator 230 at less than maximum rate in the same direction as an aiding load. In addition to the power wasted throttling down the hydraulic flow going into actuator 230, hydraulic fluid being pushed out the actuator 230 is also throttled by control valves 220 squandering potentially regenerative power and converting it into heat waste.

Adding a second set of actuators 230 for increased system reliability may magnify this power waste more than a simple factor of two. For redundancy, each control valve 220 would be independently capable of providing required power. This suggests that, when operating together, they both waste more than half the power they consume. Therefore the power wasted by adding a second set of control valves 220 may increase the power wasted and the heat generated by a factor of four.

By regulating the volume of fluid going in and out of a hydraulic actuator without throttling down flow, control valve power losses and the resulting waste heat generation may be reduced or eliminated. FIGS. 7A and 7B show an example hydraulic actuation system 300. Hydraulic actuation system 300 features a pump 310 and an actuator 320. Pump 310 is a reversible-flow hydraulic pump featuring a swashplate 312 that may be adjusted by control inputs 314. In operation, pump 310 may move a load 330 by changing the position of swashplate 312, which allows fluid to flow between the chambers of actuator 320. Thus, swashplate 312 may provide control over both displacement and flow direction.

Unlike hydraulic actuation system 200, hydraulic actuation system 300 may provide control of actuator position without the throttling power loss. However, application of this technology to IBC may be impractical due to perfor-

mance, system complexity, weight, and control issues. In particular, the high relative inertia of swashplate 312 may not be able to provide the frequency response required for IBC. In addition, a four-bladed rotor with dual redundancy would require a system of at least eight pumps total because each actuator requires a dedicated pump for control.

Thus, although the power density and jam resistance of hydraulic actuation may make hydraulic actuation suitable for application to IBC, efficiency and inertia issues may make some hydraulic actuation systems impracticable. Teachings of certain embodiments, however, recognize the capability to actuate loads in an IBC system without the wasted energy associated with hydraulic actuation system 200 or the high inertia problems associated with hydraulic actuation system 300. In particular, teachings of certain embodiments recognize the capability to efficiently and effectively actuate loads in an IBC system through the use of mechanically-programmed cams.

FIGS. 8A and 8B show a hydraulic actuation system 400 according to one example embodiment. Hydraulic actuation system 400 features a cam 410 and piston assemblies 420 and 430. Unlike hydraulic actuation system 200, hydraulic actuation system 400 does not feature any control valves to limit flow volume. Rather, piston assemblies 420 and 430 are ported directly to one another. Thus, hydraulic actuation system 400 may not suffer from the energy losses associated with hydraulic actuation system 200. In addition, unlike hydraulic actuation system 300, hydraulic actuation system 400 does not feature a swashplate and thus may not be subject to the inertia problems associated with hydraulic actuation system 300.

In operation, as shown in FIG. 8A, cam 410 pushes down the piston of piston assembly 420, which forces fluid into piston assembly 430, thus raising load 440. To lower load 440, as shown in FIG. 8B, cam 410 allows the piston of piston assembly 420 to pull up, which allows fluid to flow out of piston assembly 430, thus lowering load 440. Disregarding friction losses, raising or lowering load 440 may be 100% efficient regardless of the size of load 440.

Teachings of certain embodiments recognize the ability to reduce the power required to move a cam 410 by balancing loads between two cams 410, as shown in FIGS. 8C and 8D. In this example, a cam shaft 450 joins two cams 410 together at 180 degrees out of phase. Disregarding leakage and friction losses, the sinusoidal raising and lowering of the cylinder loads would require no additional energy to sustain motion once a constant speed of cam shaft 450 is achieved.

In addition, teachings of certain embodiments recognize the capability to program sinusoidal motion of a load by providing multiple cams of different shapes. As explained above with regard to the different categories of IBC motions, IBC motions may be expressed as specific integers of rotor revolutions (e.g., for a four-blade rotor system, 1 oscillation per revolution for cyclic motion, 2/rev for reactionless motion, 3/rev for cyclic motion, 4/rev for collective motion, 5/rev for cyclic motion, 6/rev for reactionless motion, etc.). Teachings of certain embodiments recognize the ability to program sinusoidal motion by providing a cam for each oscillation frequency and then hydraulically summing the outputs.

FIG. 9A shows a hydraulic actuation system 500 according to one example embodiment. Hydraulic actuation system 500 features a cam assembly 510, piston assemblies 520, and an actuator 530 operable to move a load 540. Each cam of cam assembly 510 is operable to oscillate a corresponding piston of piston assemblies 520 according to the sinusoidal oscillation patterns 560 shown in FIG. 9A.

In the example of FIG. 9A, cam assembly features six cams **511-516** coupled to a cam shaft **550**. Each cam **511-516** corresponds to a different oscillation frequency. Cam **511**, for example, is a single-lobed cam that oscillates piston **521** once per revolution of cam shaft **550**, as shown by sinusoidal oscillation pattern **561**. Cam **512** is a two-lobed cam that oscillates piston **522** twice per revolution of cam shaft **550**, as shown by sinusoidal oscillation pattern **562**. Cam **513** is a three-lobed cam that oscillates piston **523** three times per revolution of cam shaft **550**, as shown by sinusoidal oscillation pattern **563**. Cam **514** is a four-lobed cam that oscillates piston **524** four times per revolution of cam shaft **550**, as shown by sinusoidal oscillation pattern **564**. Cam **515** is a five-lobed cam that oscillates piston **525** five times per revolution of cam shaft **550**, as shown by sinusoidal oscillation pattern **565**. Cam **516** is a six-lobed cam that oscillates piston **526** six times per revolution of cam shaft **550**, as shown by sinusoidal oscillation pattern **566**.

A precise waveform may be generated by hydraulically summing the outputs from each piston assembly **520**. For example, FIG. 9B shows the sum of each sinusoidal oscillation pattern **560**. As shown in FIG. 9B, the sum of each sinusoidal oscillation pattern **560** may result in a summed oscillation pattern **570** that is not sinusoidal.

With these concepts in mind, teachings of certain embodiments recognize the capability to implement IBC on a rotor system, as discussed in greater detail below.

Partial-Authority IBC

FIGS. **10A-10S** show a radial fluid device **600** according to one example embodiment. Teachings of certain embodiments recognize that radial fluid device **600** may generate sinusoidal waveform amplitude and synchronization displacement control to multiple actuators from a single unit. As will be explained in greater detail below, the shape and synchronization of these sinusoidal displacement changes may be defined by the corresponding volumetric sum of hydraulic fluid required to displace each IBC actuator to replicate desired cyclic harmonic, collective harmonic, and reactionless blade motions. In this manner, radial fluid device **600** may emulate the hydraulic summation capabilities of hydraulic actuation system **500**. In addition, teachings of certain embodiments recognize that radial fluid device **600** may emulate the power conservation and regeneration capabilities of hydraulic actuation system **400** by utilizing aiding actuator loads to drive radial fluid device **600** as a hydraulic motor.

FIG. **10A** shows a side view of radial fluid device **600**, and FIG. **10B** shows a top view of radial fluid device **600**. Radial fluid device **600** features multiple stacked radial piston sections rotating together in conjunction with a common cylinder block **604** (not shown in FIGS. **10A** and **10B**). In the example of FIGS. **10A-10S**, radial fluid device **600** features stacked radial piston sections **620-660** and **620'-660'** rotating together with shaft **602** and cylinder block **604**.

As will be shown in greater detail below, shaft **602** is coupled to cylinder block **604**. In some embodiments, shaft **602** is removably coupled to cylinder block **604**. For example, different shafts **602** may have different gear splines, and an installer may choose from among different shafts **602** for use with radial fluid device **600**.

Cylinder block **604** rotates within radial fluid device **600**. In the example of FIGS. **10A-10S**, the axis of rotation of cylinder block **604** is coaxial with shaft **602**. Bearings may separate cylinder block **604** from the non-rotating body of radial fluid device **600**.

Each pump section pair (e.g., sections **620** and **620'**, **630** and **630'**, etc.) is dedicated to generating the desired waveform for a specific frequency. In the example of FIGS. **10A-**

**10S**, the pump section pairs are dedicated to generating desired waveforms for 2/rev through 6/rev. In this example, the fundamental cyclic motions (1/rev) are generated by a mechanical swashplate, such as swashplate **116** of FIG. **2**.

Although the pump section pairs in radial fluid device **600** are dedicated to generating desired waveforms for 2/rev through 6/rev, teachings of certain embodiments recognize that other fluid devices may include pump sections dedicated to generating more, fewer, or different desired waveforms. For example, the performance benefits provided by some frequencies may be minimal, and the pump sections generating these frequencies would be eliminated. As one example, a variation of radial fluid device **600** may only feature pump sections dedicated to 2/rev (reactionless) and 4/rev (collective harmonic), with the fundamental cyclic motions (1/rev) generated by a mechanical swashplate.

Separate section frequencies from each pump section pair in radial fluid device **600** may be hydraulically summed together to generate a final desired waveform to each actuator, such as described above with regard to FIG. **9B**. In particular, as will be explained in greater detail below, manifold **670** transmits the hydraulically summed fluids from radial fluid device **600** to actuators corresponding to each blade in a rotor system.

FIG. **10C** shows a cross-section view of pump section **620** along the cross-section line indicated in FIG. **10B**. In operation, pump section **620** is operable to provide a hydraulic flow that results in reactionless blade motions (2/rev) by blades **120a-120d**, as shown in FIG. **10D**. In particular, as shown in FIG. **10D**, adjacent blades **120a** and **120b** are 180 degrees out of phase, and opposite blades **120a** and **120c** are in phase. In this manner, the motion of blades in FIG. **10D** resembles the motion of blades in FIG. **5A**. As will be explained in greater detail below, teachings of certain embodiments recognize that using four equally-spaced radial pistons driven by an elliptical cam may allow the volume of fluid displaced by each piston to replicate the required 2/rev reactionless sinusoidal motion and blade synchronization.

In the example of FIG. **10C**, pump section **620** features four pistons **621a-621d**. Each piston **621a-621d** is slidably received within a corresponding cylinder associated with chambers **604a-604d**. As shown in greater detail below, each chamber **604a-604d** represents a plurality of cylinders within cylinder block **604** that are in fluid communication. Each chamber **604a-604d** may have an independent outlet port that exits radial fluid device **600** to control a different IBC actuator.

Pump section **620** also features a cam **622**. During operation, pistons **621a-621d** stroke inwards and outwards depending on the distance between cam **622** and the axis of rotation of cylinder block **604**. For example, cam **622** is an elliptical cam having two lobes. As each piston **621a-621d** moves from the transverse diameter of cam **622** towards the conjugate diameter of cam **622**, each piston **621a-621d** will be pushed closer to the axis of rotation of cylinder block **604**. Likewise, as each piston **621a-621d** moves from the conjugate diameter of cam **622** to the transverse diameter of cam **622**, each piston **621a-621d** will be pushed away from the axis of rotation of cylinder block **604**. As a result, each piston **621a-621d** reciprocates towards and away from the axis of rotation of cylinder block **604**. Each reciprocation towards and away from the axis of rotation thus includes two strokes: a down stroke and an up stroke.

In the example of FIG. **10C**, cam **622** is elliptical and thus has two lobes. The number of lobes indicates how many sinusoidal stroke motions a piston completes during one full rotation of cylinder block **604**. For example, each piston

**621a-621d** completes two sinusoidal stroke motions during one rotation of cylinder block **604**. The ability of pump section **620** to complete two sinusoidal stroke motions during one rotation corresponds to the two blade oscillations per revolution required for certain reactionless blade motions.

Rotating cam **622** may change when pistons **621a-621d** begin their strokes. For example, rotating cam **622** changes the location of the transverse diameter of cam **622** and thus changes where each piston **621a-621d** begins a down stroke. As will be explained in greater detail below, moving cam **622** relative to the corresponding cam **622'** of pump section **620'** may change the amount of time between when corresponding pistons of pump sections **620** and **620'** begin their downstrokes. Teachings of certain embodiments recognize that changing the amount of time between the downstrokes of corresponding pistons of pump sections **620** and **620'** may change the maximum accessible cylinder volume of chambers **604a-604d** and therefore change how fluid flows in and out of radial fluid device **600**.

Cam gear **623**, drive gear **624**, and cam adjuster **625** may, in combination, adjust the position of cam **622**. Cam gear **623** is coupled to cams cam **622**. Drive gear **624** interact with the teeth of cam gear **623**. Cam adjuster **625** rotates drive gear **624** such that drive gear **624** rotates cam gear **623**. As stated above, moving cams **622** changes when pistons **621a-621d** begin their strokes, and changing when pistons **621a-621d** begin their strokes can change how fluid flows in and out of radial fluid device **600**. Thus, teachings of certain embodiments recognize the ability to change how fluid flows in and out of radial fluid device **600** by changing the position of cam adjuster **625**.

In the example of FIG. 10C, cam gear **623** is a ring gear, drive gear **624** is a worm gear, and cam adjuster **625** is an electric motor. Teachings of certain embodiments recognize that an electric-driven worm gear may be particularly suitable for adjusting phase angle and amplitude for higher harmonics (e.g., 2/rev or greater) in an IBC system. In an IBC system, high-speed changes in phase angle and amplitude may not be required or even desired for higher harmonics. For example, slow changes in elliptical cam phase angle may provide time for failure modes to be identified and bypassed before undesirable blade motions are generated. In addition, a small-diameter worm gear running on a large-diameter ring gear may provide a high-gear reduction, thus reducing the torque of the electric motor required and providing irreversibility in the event of a motor failure. In the event an electric motor should fail, the oscillatory motion may be nullified by the still operating pump section (e.g., pump section **620'**) by indexing it's cam to an opposing phase position.

FIGS. 10E, 10F, and 10G show pump sections **620** and **620'** in operation with their cams **622** and **622'** in phase. FIG. 10E shows a cross-section view of pump section **620** along the cross-section line indicated in FIG. 10A, FIG. 10F shows a cross-section view of pump section **620'** along the cross-section line indicated in FIG. 10A, and FIG. 10G shows the resulting blade angle for blade **120a** that is produced by pump sections **620** and **620'**.

In operation, pump section **620**, is operable to provide a hydraulic flow that results in reactionless blade motions (2/rev) by blades **120a-120d**. As shown in FIG. 10F, pump section **620'** features pistons **621a'-621d'**, a cam **622'**, a cam gear **623'**, a drive gear **624'**, and a cam adjuster **625'**. Each piston **621a'-621d'** is slidably received within a corresponding cylinder associated with chambers **604a-604d**. In this manner, corresponding pistons **621a** and **621a'** share chamber **604a**, corresponding pistons **621b** and **621b'** share chamber

**604b**, corresponding pistons **621c** and **621c'** share chamber **604c**, and corresponding pistons **621d** and **621d'** share chamber **604d**.

Cam **622'** is elliptical and thus has two lobes. Each piston **621a'-621d'** completes two sinusoidal stroke motions during one rotation of cylinder block **604**. The ability of pump section **620'** to complete two sinusoidal stroke motions during one rotation corresponds to the two blade oscillations per revolution required for certain reactionless blade motions.

Cam gear **623'**, drive gear **624'**, and cam adjuster **625'** may, in combination, adjust the position of cam **622'**. In some embodiments, the relative positions of cams **622** and **622'** may be adjusted independently. For example, cams **622** and **622'** may be rotated in either the same direction or opposite directions, and the distance of rotation of cam **622** may not necessarily match the distance of rotation of **622'**.

FIG. 10G shows the resulting blade angle for blade **120a** that is produced by pump sections **620** and **620'** when cams **622** and **622'** are in phase. In this example, both pump sections **620** and **620'** are in phase such that pistons **621a** and **621a'** complete their upstrokes and begin their downstrokes at zero degrees and 180 degrees azimuth. In this configuration, the sum of the sinusoidal waves generated by pump sections **620** and **620'** is effectively double the contributing sinusoidal waves.

FIGS. 10H, 10I, and 10J show pump sections **620** and **620'** in operation when their cams **622** and **622'** are 90 degrees out of phase. FIG. 10E shows a cross-section view of pump section **620** along the cross-section line indicated in FIG. 10A, FIG. 10F shows a cross-section view of pump section **620'** along the cross-section line indicated in FIG. 10A, and FIG. 10G shows the resulting blade angle for blade **120a** that is produced by pump sections **620** and **620'** when cams **622** and **622'** are 90 degrees out of phase. As shown in FIG. 10H, cam **622** has been rotated 90 degrees relative to its position shown in FIG. 10E.

In this example, both pump sections **620** and **620'** are 90 degrees out of phase such that pistons **621a** and **621a'** complete their upstrokes and begin their downstrokes 90 degrees apart. In this configuration, the contributing sinusoidal waves generated by pump sections **620** and **620'** effectively cancel out. Thus, pump sections **620** and **620'** effectively have no impact on flow in or out of chamber **604a** and therefore do not cause any reactionless motions by blade **120a**.

The examples of FIGS. 10G and 10J show how rotating cams **622** and **622'** in opposite directions relative to one another may change the effective flow volume of chamber **604a** and thus change the amplitude of the total sinusoidal wave produced by the combination of pump sections **620** and **620'**. Teachings of certain embodiments recognize the ability to change the phase of the total sinusoidal wave produced by the combination of pump sections **620** and **620'** in addition to changing the amplitude. In particular, rotating cams **622** and **622'** in the same direction may change when the total sinusoidal wave reaches peak amplitude without changing the magnitude of the peak amplitude.

In the example of FIGS. 10C-10J, pump sections **620** and **620'** include two-lobed (elliptical) cams capable of generating certain reactionless blade motions. Teachings of certain embodiments recognize that radial fluid device **600** may also include additional pump sections capable of generating different blade motions.

FIG. 10K shows a cross-section view of pump section **630** along the cross-section line indicated in FIG. 10B. In operation, pump section **630** is operable to provide a hydraulic flow that results in cyclic blade motions (3/rev) by blades **120a-**

11

120d, as shown in FIG. 10L. In this manner, the motion of blades in FIG. 10L resembles the motion of blades in FIG. 3B.

Radial fluid device 600 also includes a corresponding pump section 630'. Pump sections 630 and 630' may operate together to generate cyclic blade motions (3/rev) similarly to how pump sections 620 and 620' operate together to generate reactionless blade motions (2/rev).

As shown in FIG. 10K, pump section 630 features pistons 631a-631d, a cam 632, a cam gear 633, a drive gear 634, and a cam adjuster 635. Each piston 631a-631d is slidably received within a corresponding cylinder associated with chambers 604a-604d. Similarly, each piston 631a'-631d' of pump section 630' is also slidably received within a corresponding cylinder associated with chambers 604a-604d. In this manner, corresponding pistons 631a and 631a' share chamber 604a, corresponding pistons 631b and 631b' share chamber 604b, corresponding pistons 631c and 631c' share chamber 604c, and corresponding pistons 631d and 631d' share chamber 604d. In addition, pistons 631a and 631a', pistons 631b and 631b', pistons 631c and 631c', and pistons 631d and 631d' share chambers with pistons of the other pump sections of radial fluid device 600.

Cam 632 has three lobes. Each piston 631a-631d completes three sinusoidal stroke motions during one rotation of cylinder block 604. The ability of pump section 630 to complete three sinusoidal stroke motions during one rotation corresponds to the three blade oscillations per revolution required for certain cyclic blade motions.

Cam gear 633, drive gear 634, and cam adjuster 635 may, in combination, adjust the position of cam 632. In some embodiments, the relative positions of cams 632 and 632' may be adjusted independently. For example, cams 632 and 632' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 632 may not necessarily match the distance of rotation of 632'.

FIG. 10M shows a cross-section view of pump section 640 along the cross-section line indicated in FIG. 10B. In operation, pump section 640 is operable to provide a hydraulic flow that results in collective blade motions (4/rev) by blades 120a-120d, as shown in FIG. 10N. In this manner, the motion of blades in FIG. 10N resembles the motion of blades in FIGS. 4A-4D.

Radial fluid device 600 also includes a corresponding pump section 640'. Pump sections 640 and 640' may operate together to generate collective blade motions (4/rev) similarly to how pump sections 620 and 620' operate together to generate reactionless blade motions (2/rev).

As shown in FIG. 10M, pump section 640 features pistons 641a-641d, a cam 642, a cam gear 643, a drive gear 644, and a cam adjuster 645. Each piston 641a-641d is slidably received within a corresponding cylinder associated with chambers 604a-604d. Similarly, each piston 641a'-641d' of pump section 640' is also slidably received within a corresponding cylinder associated with chambers 604a-604d. In this manner, corresponding pistons 641a and 641a' share chamber 604a, corresponding pistons 641b and 641b' share chamber 604b, corresponding pistons 641c and 641c' share chamber 604c, and corresponding pistons 641d and 641d' share chamber 604d. In addition, pistons 641a and 641a', pistons 641b and 641b', pistons 641c and 641c', and pistons 641d and 641d' share chambers with pistons of the other pump sections of radial fluid device 600.

Cam 642 has four lobes. Each piston 641a-641d completes four sinusoidal stroke motions during one rotation of cylinder block 604. The ability of pump section 640 to complete four

12

sinusoidal stroke motions during one rotation corresponds to the four blade oscillations per revolution required for certain collective blade motions.

Cam gear 643, drive gear 644, and cam adjuster 645 may, in combination, adjust the position of cam 642. In some embodiments, the relative positions of cams 642 and 642' may be adjusted independently. For example, cams 642 and 642' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 642 may not necessarily match the distance of rotation of 642'.

FIG. 10O shows a cross-section view of pump section 650 along the cross-section line indicated in FIG. 10B. In operation, pump section 650 is operable to provide a hydraulic flow that results in cyclic blade motions (5/rev) by blades 120a-120d, as shown in FIG. 10P. In this manner, the motion of blades in FIG. 10P resembles the motion of blades in FIG. 3C.

Radial fluid device 600 also includes a corresponding pump section 650'. Pump sections 650 and 650' may operate together to generate cyclic blade motions (5/rev) similarly to how pump sections 620 and 620' operate together to generate reactionless blade motions (2/rev).

As shown in FIG. 10M, pump section 650 features pistons 651a-651d, a cam 652, a cam gear 653, a drive gear 654, and a cam adjuster 655. Each piston 651a-651d is slidably received within a corresponding cylinder associated with chambers 604a-604d. Similarly, each piston 651a'-651d' of pump section 650' is also slidably received within a corresponding cylinder associated with chambers 604a-604d. In this manner, corresponding pistons 651a and 651a' share chamber 604a, corresponding pistons 651b and 651b' share chamber 604b, corresponding pistons 651c and 651c' share chamber 604c, and corresponding pistons 651d and 651d' share chamber 604d. In addition, pistons 651a and 651a', pistons 651b and 651b', pistons 651c and 651c', and pistons 651d and 651d' share chambers with pistons of the other pump sections of radial fluid device 600.

Cam 652 has five lobes. Each piston 651a-651d completes five sinusoidal stroke motions during one rotation of cylinder block 604. The ability of pump section 650 to complete five sinusoidal stroke motions during one rotation corresponds to the five blade oscillations per revolution required for certain cyclic blade motions.

Cam gear 653, drive gear 654, and cam adjuster 655 may, in combination, adjust the position of cam 652. In some embodiments, the relative positions of cams 652 and 652' may be adjusted independently. For example, cams 652 and 652' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 652 may not necessarily match the distance of rotation of 652'.

FIG. 10Q shows a cross-section view of pump section 660 along the cross-section line indicated in FIG. 10B. In operation, pump section 660 is operable to provide a hydraulic flow that results in reactionless blade motions (6/rev) by blades 120a-120d, as shown in FIG. 10R. In this manner, the motion of blades in FIG. 10R resembles the motion of blades in FIG. 5B.

Radial fluid device 600 also includes a corresponding pump section 660'. Pump sections 660 and 660' may operate together to generate reactionless blade motions (6/rev) similarly to how pump sections 620 and 620' operate together to generate reactionless blade motions (2/rev).

As shown in FIG. 10M, pump section 660 features pistons 661a-661d, a cam 662, a cam gear 663, a drive gear 664, and a cam adjuster 665. Each piston 661a-661d is slidably received within a corresponding cylinder associated with chambers 604a-604d. Similarly, each piston 661a'-661d' of pump section 660' is also slidably received within a corre-



13

sponding cylinder associated with chambers **604a-604d**. In this manner, corresponding pistons **661a** and **661a'** share chamber **604a**, corresponding pistons **661b** and **661b'** share chamber **604b**, corresponding pistons **661c** and **661c'** share chamber **604c**, and corresponding pistons **661d** and **661d'** share chamber **604d**. In addition, pistons **661a** and **661a'**, pistons **661b** and **661b'**, pistons **661c** and **661c'**, and pistons **661d** and **661d'** share chambers with pistons of the other pump sections of radial fluid device **600**.

Cam **662** has six lobes. Each piston **661a-661d** completes six sinusoidal stroke motions during one rotation of cylinder block **604**. The ability of pump section **660** to complete six sinusoidal stroke motions during one rotation corresponds to the six blade oscillations per revolution required for certain reactionless blade motions.

Cam gear **663**, drive gear **664**, and cam adjuster **665** may, in combination, adjust the position of cam **662**. In some embodiments, the relative positions of cams **662** and **662'** may be adjusted independently. For example, cams **662** and **662'** may be rotated in either the same direction or opposite directions, and the distance of rotation of cam **662** may not necessarily match the distance of rotation of **662'**.

FIG. **10S** shows a cross-section view of radial fluid device **600** along the cross-section line indicated in FIG. **10B**. As shown in FIG. **10S**, all pump sections generating frequencies 2/rev through 6/rev are situated about the same cylinder block **604**. In addition, all pump sections share the same chambers **604a-604d**. Each chamber **604a-604d** is ported out of radial fluid device **600** through manifold **670**. Manifold **670** may enable fluid communication between each chamber **604a-604d** and a corresponding actuator with rotor blades **120a-120d** (e.g., fluid communication between chamber **604a** and the actuator associated with rotor blade **120a**).

Teachings of certain embodiments recognize that radial fluid device **600** may provide for IBC in a relatively compact space. For example, a 9000 pound helicopter featuring a four-bladed rotor system operating at 3000 PSI operating pressure may utilize a radial fluid device such as radial fluid device **600** that measures approximately 6 inches by 6 inches by 11 inches (not including the cam adjusters). In this example, pump sections **620** and **620'** may be sized to provide 20% of normal cyclic authority while all other frequencies may be sized to provide 10% of normal cyclic authority.

In some embodiments, cylinder block **604** may rotate at the same speed as drive shaft **112b**. Teachings of certain embodiments recognize that rotating cylinder block **604** at the same speed as drive shaft **112b** may allow harmonic outputs from radial fluid device **600** to be synchronized with the rotor blades **120a-120d** rotating about drive shaft **112b**. In the example of FIG. **10S**, an exterior power source rotates shaft **602** at the same speed as drive shaft **112b**, which causes cylinder block **604** to also rotate at the same speed. Teachings of certain embodiments recognize that radial fluid device **600** may be well suited to operate at the same speed as drive shaft **112b**. For example, helicopter hydraulic pumps in other settings may operate at approximately 5000 RPM and industrial radial pumps of similar displacements as radial fluid device **600** may operate at approximately 1500 RPM, whereas as rotor speeds are typically lower than these speeds (e.g., 400 to 500 RPM).

In the example of FIGS. **10A-10S**, radial fluid device **600** is configured to provide IBC in a four blade rotor system. Teachings of certain embodiments recognize, however, recognize that the concepts described with regard to radial fluid device **600** may be adapted to support IBC for rotor systems with more or fewer blades (e.g., two blades, three blades, five blades, six blades, seven blades, etc.) by adapting the arrange-

14

ment of pistons, cams, and porting. For example, FIGS. **11A-11K** shows a radial fluid device **700** configured to provide IBC in a five blade rotor system.

FIG. **11A** shows a top view of radial fluid device **700**. Radial fluid device **700** features multiple stacked radial piston sections rotating together in conjunction with a common cylinder block **704** (not shown in FIG. **10A**). In the example of FIGS. **11A-11J**, radial fluid device **700** features stacked radial piston sections **720-760** and **720'-760'** rotating together with shaft **702** and cylinder block **704**.

As will be shown in greater detail below, shaft **702** is coupled to cylinder block **704**. In some embodiments, shaft **702** is removably coupled to cylinder block **704**. For example, different shafts **702** may have different gear splines, and an installer may choose from among different shafts **702** for use with radial fluid device **600**.

Cylinder block **704** rotates within radial fluid device **700**. In the example of FIGS. **11A-11J**, the axis of rotation of cylinder block **704** is coaxial with shaft **702**. Bearings may separate cylinder block **704** from the non-rotating body of radial fluid device **700**.

Each pump section pair (e.g., sections **720** and **720'**, **730** and **730'**, etc.) is dedicated to generating the desired waveform for a specific frequency. In the example of FIGS. **11A-11J**, the pump section pairs are dedicated to generating desired waveforms for 2/rev through 6/rev. In this example, the fundamental cyclic motions (1/rev) are generated by a mechanical swashplate, such as swashplate **116** of FIG. **2**.

Although the pump section pairs in radial fluid device **700** are dedicated to generating desired waveforms for 2/rev through 6/rev, teachings of certain embodiments recognize that other fluid devices may include pump sections dedicated to generating more, fewer, or different desired waveforms. For example, the performance benefits provided by some frequencies may be minimal, and the pump sections generating these frequencies would be eliminated. As one example, a variation of radial fluid device **700** may only feature pump sections dedicated to 2/rev (reactionless) and 4/rev (collective harmonic), with the fundamental cyclic motions (1/rev) generated by a mechanical swashplate.

Separate section frequencies from each pump section pair in radial fluid device **700** may be hydraulically summed together to generate a final desired waveform to each actuator, such as described above with regard to FIG. **9B**. In particular, as will be explained in greater detail below, manifold **770** transmits the hydraulically summed fluids from radial fluid device **700** to actuators corresponding to each blade in a rotor system.

In this example embodiments, pump sections **730-760** and **730'-760'** of radial fluid device **700** may operate in a similar manner to pump sections **630-660** and **630'-660'** of radial fluid device **600**. For example, FIG. **11B** shows a cross-section view of pump section **730** along the cross-section line indicated in FIG. **11A**. In operation, pump section **730** is operable to provide a hydraulic flow that results in cyclic blade motions (3/rev) by blades **120a-120d**, as shown in FIG. **11C**. In this manner, the motion of blades in FIG. **11C** resembles the motion of blades in FIG. **3B**.

Radial fluid device **700** also includes a corresponding pump section **730'**. Pump sections **730** and **730'** may operate together to generate cyclic blade motions (3/rev) similarly to how pump sections **730** and **730'** operate together to generate cyclic blade motions (3/rev).

As shown in FIG. **11B**, pump section **730** features pistons **731a-731e**, a cam **732**, a cam gear **733**, a drive gear **734**, and a cam adjuster **735**. Each piston **731a-731e** is slidably received within a corresponding cylinder associated with

15

chambers 704a-704e. Similarly, each piston 731a'-731e' of pump section 730' is also slidably received within a corresponding cylinder associated with chambers 704a-704e. In this manner, corresponding pistons 731a and 731a' share chamber 704a, corresponding pistons 731b and 731b' share chamber 704b, corresponding pistons 731c and 731c' share chamber 704c, corresponding pistons 731d and 731d' share chamber 704d, and corresponding pistons 731e and 731e' share chamber 704e. In addition, pistons 731a and 731a', pistons 731b and 731b', pistons 731c and 731c', pistons 731d and 731d', and pistons 731e and 731e' share chambers with pistons of the other pump sections of radial fluid device 700.

Cam gear 733, drive gear 734, and cam adjuster 735 may, in combination, adjust the position of cam 732. In some embodiments, the relative positions of cams 732 and 732' may be adjusted independently. For example, cams 732 and 732' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 732 may not necessarily match the distance of rotation of 732'.

FIG. 11D shows a cross-section view of pump section 740 along the cross-section line indicated in FIG. 11A. In operation, pump section 740 is operable to provide a hydraulic flow that results in collective blade motions (4/rev) by blades 120a-120d, as shown in FIG. 11E. In this manner, the motion of blades in FIG. 11E resembles the motion of blades in FIGS. 4A-4D.

Radial fluid device 700 also includes a corresponding pump section 740'. Pump sections 740 and 740' may operate together to generate collective blade motions (4/rev) similarly to how pump sections 640 and 640' operate together to generate collective blade motions (4/rev).

As shown in FIG. 11D, pump section 740 features pistons 741a-741e, a cam 742, a cam gear 743, a drive gear 744, and a cam adjuster 745. Each piston 741a-741e is slidably received within a corresponding cylinder associated with chambers 704a-704e. Similarly, each piston 741a'-741e' of pump section 740' is also slidably received within a corresponding cylinder associated with chambers 704a-704e. In this manner, corresponding pistons 741a and 741a' share chamber 704a, corresponding pistons 741b and 741b' share chamber 704b, corresponding pistons 741c and 741c' share chamber 704c, corresponding pistons 741d and 741d' share chamber 704d, and corresponding pistons 741e and 741e' share chamber 704e. In addition, pistons 741a and 741a', pistons 741b and 741b', pistons 741c and 741c', pistons 741d and 741d', and pistons 741e and 741e' share chambers with pistons of the other pump sections of radial fluid device 700.

Cam gear 743, drive gear 744, and cam adjuster 745 may, in combination, adjust the position of cam 742. In some embodiments, the relative positions of cams 742 and 742' may be adjusted independently. For example, cams 742 and 742' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 742 may not necessarily match the distance of rotation of 742'.

FIG. 11F shows a cross-section view of pump section 750 along the cross-section line indicated in FIG. 11A. In operation, pump section 750 is operable to provide a hydraulic flow that results in cyclic blade motions (5/rev) by blades 120a-120d, as shown in FIG. 11G. In this manner, the motion of blades in FIG. 11G resembles the motion of blades in FIG. 3C.

Radial fluid device 700 also includes a corresponding pump section 750'. Pump sections 750 and 750' may operate together to generate cyclic blade motions (5/rev) similarly to how pump sections 650 and 650' operate together to generate cyclic blade motions (5/rev).

16

As shown in FIG. 11F, pump section 750 features pistons 751a-751e, a cam 752, a cam gear 753, a drive gear 754, and a cam adjuster 755. Each piston 751a-751e is slidably received within a corresponding cylinder associated with chambers 704a-704e. Similarly, each piston 751a'-751e' of pump section 750' is also slidably received within a corresponding cylinder associated with chambers 704a-704e. In this manner, corresponding pistons 751a and 751a' share chamber 704a, corresponding pistons 751b and 751b' share chamber 704b, corresponding pistons 751c and 751c' share chamber 704c, corresponding pistons 751d and 751d' share chamber 704d, and corresponding pistons 751e and 751e' share chamber 704e. In addition, pistons 751a and 751a', pistons 751b and 751b', pistons 751c and 751c', pistons 751d and 751d', and pistons 751e and 751e' share chambers with pistons of the other pump sections of radial fluid device 700.

Cam gear 753, drive gear 754, and cam adjuster 755 may, in combination, adjust the position of cam 752. In some embodiments, the relative positions of cams 752 and 752' may be adjusted independently. For example, cams 752 and 752' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 752 may not necessarily match the distance of rotation of 752'.

FIG. 11H shows a cross-section view of pump section 760 along the cross-section line indicated in FIG. 11A. In operation, pump section 760 is operable to provide a hydraulic flow that results in reactionless blade motions (6/rev) by blades 120a-120d, as shown in FIG. 11I. In this manner, the motion of blades in FIG. 11I resembles the motion of blades in FIG. 5B.

Radial fluid device 700 also includes a corresponding pump section 760'. Pump sections 760 and 760' may operate together to generate reactionless blade motions (6/rev) similarly to how pump sections 660 and 660' operate together to generate reactionless blade motions (6/rev).

As shown in FIG. 11H, pump section 760 features pistons 761a-761e, a cam 762, a cam gear 763, a drive gear 764, and a cam adjuster 765. Each piston 761a-761e is slidably received within a corresponding cylinder associated with chambers 704a-704e. Similarly, each piston 761a'-761e' of pump section 760' is also slidably received within a corresponding cylinder associated with chambers 704a-704e. In this manner, corresponding pistons 761a and 761a' share chamber 704a, corresponding pistons 761b and 761b' share chamber 704b, corresponding pistons 761c and 761c' share chamber 704c, corresponding pistons 761d and 761d' share chamber 704d, and corresponding pistons 761e and 761e' share chamber 704e. In addition, pistons 761a and 761a', pistons 761b and 761b', pistons 761c and 761c', pistons 761d and 761d', and pistons 761e and 761e' share chambers with pistons of the other pump sections of radial fluid device 700.

Cam gear 763, drive gear 764, and cam adjuster 765 may, in combination, adjust the position of cam 762. In some embodiments, the relative positions of cams 762 and 762' may be adjusted independently. For example, cams 762 and 762' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 762 may not necessarily match the distance of rotation of 762'.

In the examples of FIGS. 11B-11I, each piston is ported sequentially to a corresponding blade actuator with the 72 degree radial spacing for the five-blade frequencies of 3/rev, 4/rev, 5/rev, and 6/rev. For 2/rev reactionless motion using an elliptical cam, however, teachings of certain embodiments recognize that piston ports may be crossed in pump section 720 for a five-bladed rotor system. In particular, cross-porting may allow fluid device 700 to use pistons with 72 degree

17

spacing to generate blade motions of 144 degree spacing, which may satisfy requirements of 2/rev reactionless motions.

FIG. 11J shows a cross-section view of pump section 720 along the cross-section line indicated in FIG. 11A. In operation, pump section 720 is operable to provide a hydraulic flow that results in reactionless blade motions (2/rev) by blades 120a-120d, as shown in FIG. 11K. In this manner, the motion of blades in FIG. 11K resembles the motion of blades in FIG. 5A.

Radial fluid device 700 also includes a corresponding pump section 720'. Pump sections 720 and 720' may operate together to generate reactionless blade motions (2/rev) similarly to how pump sections 620 and 620' operate together to generate reactionless blade motions (2/rev), except that the piston ports in pump section 720 are crossed for a five-bladed rotor system.

As shown in FIG. 11J, pump section 720 features pistons 721a-721e, a cam 722, a cam gear 723, a drive gear 724, and a cam adjuster 725. Each piston 721a-721e is slidably received within a cylinder associated with chambers 704a-704e. However, unlike pump sections 730-760, the correspondence between pistons 721a-721e and chambers 704a-704e is crossed for some pistons. In the example of FIG. 11J, piston 721a is slidably received within a cylinder associated with chamber 704a, piston 721b is slidably received within a cylinder associated with chamber 704c, piston 721c is slidably received within a cylinder associated with chamber 704e, piston 721d is slidably received within a cylinder associated with chamber 704b, and piston 721e is slidably received within a cylinder associated with chamber 704d. Similarly, piston 721a' is slidably received within a cylinder associated with chamber 704a, piston 721b' is slidably received within a cylinder associated with chamber 704c, piston 721c' is slidably received within a cylinder associated with chamber 704e, piston 721d' is slidably received within a cylinder associated with chamber 704b, and piston 721e' is slidably received within a cylinder associated with chamber 704d. In this manner, corresponding pistons 721a and 721a' share chamber 704a, corresponding pistons 721b and 721b' share chamber 704c, corresponding pistons 721c and 721c' share chamber 704e, corresponding pistons 721d and 721d' share chamber 704b, and corresponding pistons 721e and 721e' share chamber 704d. In addition, pistons 721a and 721a', pistons 721b and 721b', pistons 721c and 721c', pistons 721d and 721d', and pistons 721e and 721e' share chambers with pistons of the other pump sections of radial fluid device 700.

Cam gear 723, drive gear 724, and cam adjuster 725 may, in combination, adjust the position of cam 722. In some embodiments, the relative positions of cams 722 and 722' may be adjusted independently. For example, cams 722 and 722' may be rotated in either the same direction or opposite directions, and the distance of rotation of cam 722 may not necessarily match the distance of rotation of 722'. Implementing Partial-Authority IBC

As stated above, radial fluid device 600 may provide sinusoidal waveform amplitude and synchronization displacement control to multiple actuators for use in a partial-authority IBC system. For example, radial fluid device 600 may include pump section pairs dedicated to generating desired waveforms for 2/rev through 6/rev. In this example, the fundamental cyclic motions (1/rev) are generated by a mechanical swashplate, such as swashplate 116 of FIG. 2. As will be explained in greater detail below, teachings of certain embodiments recognize the capability to convert harmonic

18

pressure changes in hydraulic fluid within radial fluid device 600 into movements of blades 120a-120d.

FIG. 12A shows an IBC system 800 according to one example embodiment. IBC system 800 is a partial-authority IBC system that features radial fluid device 600, a hydraulic control manifold 810, a hydraulic swivel 820, four pitch link actuators 830a-830d (corresponding to rotor blades 120a-120d), a hydraulic pump 840, a hydraulic reservoir 850, and a heat exchanger 860.

As shown in FIGS. 12A-12E, IBC system 800 may include a variety of fluid lines that provide fluid communication between multiple components. For convenience, some of these fluid lines have been labeled "a," "b," "c," "d," "e," or "f." In these example embodiments, labels "a"-"d" correspond with chambers 604a-604d and blades 120a-120d. For example, fluid line "a" may represent a fluid line in the path between chamber 604a and blade 120a. Fluid line "e" may refer to system fluid, and fluid line "f" may refer to return fluid, both of which are described in greater detail below.

In operation, according to one example embodiment, radial fluid device 600 provides hydraulic fluid to hydraulic control manifold 810. Hydraulic control manifold directs the fluid through hydraulic swivel 820, which is configured to transfer the fluid flow from the fixed-frame portion of the rotorcraft to the rotating-frame portion of the rotorcraft. In one example embodiment, hydraulic swivel 820 provides the fluid up along the drive shaft to pitch link actuators 830a-830d, which converts pressure changes in the supplied hydraulic fluid into movements of rotor blades 120a-120d.

In addition to providing fluid from radial fluid device 600 to pitch link actuators 830a-830d, IBC system 800 also provides system fluid from hydraulic pump 840 to pitch link actuators 830a-830d. This system fluid represents a constant-pressure fluid supply. Teachings of certain embodiments recognize that the supply fluid may not necessarily stay constant, such as due to leakage or other effects that may change the pressure of the supply fluid. The supply fluid may be provided to pitch link actuators 830a-830d to provide a balance against the pressures of the hydraulic fluid from radial fluid device 600. Excess fluid may also be accumulated through hydraulic control manifold 810 and hydraulic swivel 820, passed through heat exchanger 860, and stored in hydraulic reservoir 850 before being resupplied to hydraulic pump 840.

FIG. 12B shows hydraulic control manifold 810 according to one example embodiment. Hydraulic control manifold 810 features valves 812 and control ports 814.

In operation, according to one example embodiment, hydraulic control manifold 810 receives fluid from chambers 604a-604d of radial fluid device 600 and communicates the fluid to valves 812 and control ports 814. In this example embodiment, hydraulic control manifold 810 receives the fluid from chambers 604a-604d through manifold 670, which rotates with cylinder block 604. Manifold 670 includes ports for each chamber 604a-604d. In addition, manifold 670 includes seals around each port for chambers 604a-604d. Furthermore, manifold 670 includes return ports to accumulate leaking hydraulic fluid and return the accumulated hydraulic fluid to reservoir 850.

Radial fluid device 600 may not include provisions for independently trimming pitch link actuator stroke position to equalize their lengths and maintain IBC operation about a center stroke. Accordingly, hydraulic control manifold 810 may include valves 812 operable to trim the position of each pitch link actuator 830a-830d and to compensate for leaking hydraulic fluid. In one example embodiment, valves 812 are three-way direct drive valves.

19

Valves **812** may add supply fluid to fluid lines a-d if the fluid pressure falls below a threshold. Alternatively, valves **812** may remove fluid from fluid lines a-d associated if the fluid pressure rises about a threshold. In one example embodiment, valves **812** receives measurements from position sensors associated with pitch link actuators **830a-830d** and then adds fluid to or removes fluid from the fluid lines a-d based on the received measurements. The measurements from the position sensors may indicate, for example, the amount of fluid that has leaked from various fluid lines within IBC system **800**. As another example, the measurements from the position sensors may indicate whether fluid line pressure should be adjusted to trim the position of each pitch link actuators **830a-830d**.

In one example embodiment, valves **812** may adjust for drift and leakage in IBC system **800**, but valves **812** may not drive high-frequency changes in system pressure. Rather, high-frequency changes may be implemented by radial fluid device **600**. Teachings of certain embodiments recognize that only using valves for low-frequency changes in system pressure may reduce the necessary size of the valves and increase longevity of the valves.

Control ports **814** communicate fluid between hydraulic control manifold **810** and hydraulic swivel **820**. Teachings of certain embodiments recognize that control ports **814** may also terminate fluid flow in the event of some system failures. In the example of FIG. 12B, each control port **814** is equipped with a solenoid bypass valve. In the event of a partial-authority system failure requiring isolation from the conventional flight control system, for example, IBC system **800** may remove power to the solenoid bypass valves associated with each control port **814**. In response, control ports **814** cut off pressure to their pressure relief/bypass valves, causing them to redirect system fluid to the hydraulic fluid return lines f that lead back to reservoir **850**. Redirecting system fluid prevents the system fluid from reaching the pitch link actuators **830a-830d**, which as will be explained in greater detail below, causes the pitch link actuators **830a-830d** to lock at their center stroke position.

FIG. 12C shows hydraulic swivel **820** according to one example embodiment. Hydraulic swivel **820** includes a rotating portion **822** and a stationary portion **824**. Rotating portion **822** includes ports **822a-822d** that communicates fluid between pitch link actuators **830a-830d** and non-rotating portion **824**. Rotating portion **822** also includes port **822e**, which communicates system fluid between pitch link actuators **830a-830d** and non-rotating portion **824**. Rotating portion **822** includes port **822f**, which communicates return fluid between pitch link actuators **830a-830d** and non-rotating portion **824**.

Rotating portion also includes rotary seals **823** between each port **822a-822f**. Teachings of certain embodiments recognize that providing both port **822f** for return fluid and seals **823** may extend seal life and reduce or eliminate issues associated with nuisance leakage.

Rotating portion also includes wiring for communicating signals from pitch link actuators **830a-830d** to the non-rotating portions of IBC system **800**. In one example embodiment, the wiring includes wires for each position sensor associated with the pitch link actuators **830a-830d** plus three common wires providing excitation power.

Stationary portion **824** includes fluid lines **824a-824d** that communicates fluid between ports **822a-822d** and fluid lines a-d. Stationary portion **824** also includes fluid line **824e**, which communicates fluid between port **822e** and fluid line e. Stationary portion **824** includes fluid line **824f**, which communicates fluid between port **822f** and fluid line f.

20

FIG. 12D shows pitch link actuator **830a** according to one example embodiment. Pitch link actuator **830a** is operable to change the position of blade **120a** during operation of rotorcraft **100**. Similarly, pitch link actuators **830b-830d** are operable to change the positions of blades **120b-120d**, respectively.

In one example embodiment, pitch link actuator **830a** may be coupled between hub **114** and swashplate **116** such that pitch link actuator **830a** may change the distance between hub **114** and swashplate **116**. In this example, pitch link actuator **830a** is coupled between hub **114** and swashplate **116** but not necessarily coupled to hub **114** and/or swashplate **116**. For example, pitch link actuator **830a** may be coupled to other components in mechanical communication with hub **114** and/or swashplate **116**. In addition, pitch link actuator **830a** may only change one measurement of a distance between hub **114** and swashplate **116**. For example, pitch link actuator **830a** may change the distance between hub **114** and swashplate **116** proximate to pitch link actuator **830a**, whereas the distance between hub **114** and swashplate **116** proximate to pitch link actuator **830b** may remain the same.

In the example of FIG. 12D, pitch link actuator **830a** includes a linear hydraulic actuator that includes a piston **832a** that separates a control chamber **831a** from a system chamber **833a**. Control chamber **831a** receives fluid from line a. System chamber **833a** receives controlled system fluid from line e. In operation, piston **832a** moves in response to a pressure difference between fluid in control chamber **831a** and fluid in system chamber **833a**.

In the example of FIG. 12D, piston **832a** is unbalanced. The piston area on the side of control chamber **831a** is greater than the piston area on the side of system chamber **833a**. In this example, system fluid in system chamber **833a** may prevent hydraulic cavitation from occurring by creating a constant-force, hydraulic-spring effect on piston **832a**.

Teachings of certain embodiments recognize that pitch link actuators **830a-830d** may conserve hydraulic power during operation. For example, during higher-harmonic cyclic and reactionless motions, the total net flow used by pitch link actuators **830a-830d** may be near zero due to the summed opposing sinusoidal flow demands canceling. For example, during reactionless motions, a downstroke by piston **832a** may be offset by an upstroke by piston **832b**.

On the other hand, higher-harmonic collective motions may require significantly more fluid to move all blades sinusoidally in unison. In this example, pitch link actuators **830a-830d** may push a large volume of fluid back into the remaining components of IBC system **800** or pull a large volume of fluid out of the remaining components of IBC system **800**. Teachings of certain embodiments recognize, however, that hydraulic accumulator may capture and recover this hydraulic energy on the rotor-frame side of IBC system **800**. In the example of FIG. 12A, the hydraulic accumulator is connected to the system fluid line e.

In the example of FIG. 12D, pitch link actuator **830a** also includes a position sensor **834a**. Position sensor **834a** may measure the displacement distance of piston **832a**. One example of position sensor **834a** may include a linear variable differential transformer. Position sensor **834a** may be used as part of a feedback control system. For example, the cams of radial fluid device **600** may be programmed so as to produce an expected displacement distance of piston **832a**. If position sensor **834a** measures a displacement distance different from the expected displacement distance, one or more problems could be the cause. For example, IBC system **800** could be leaking fluid, which may change the pressure difference between fluid in chambers **831a** and **833a**, which would change the displacement distance of piston **832a**. In response,

IBC system **800** may take one or more corrective actions. As one example, the cams of radial fluid device **600** may be repositioned to achieve the expected displacement distance. As another example, valves **812** may add fluid to or remove fluid from the fluid lines (e.g., fluid lines a-e) to adjust the fluid pressures in pitch link actuator **830a**. In some embodiments, adjusting the cams of radial fluid device **600** may be more appropriate for making large changes in fluid pressure, whereas adjusting valves **812** may be more appropriate for smaller changes or trimming of fluid pressure.

In the example of FIG. **12D**, pitch link actuator **830a** also includes a stroke lock **836a**. Stroke lock **836a** may prevent piston **832a** from moving in the event of system failure. As shown in FIG. **12D**, stroke lock **836a** separates the system fluid from a spring. The spring provides an opposing force to the pressure from the system fluid. If, for example, the pressure from the system fluid is reduced or eliminated, force from the spring pushes the spring lock **836a** towards piston **832a** and prevents piston **832a** from moving, as shown in FIG. **12E**. Such a scenario might occur, for example, if control port **814e** prevents system fluid from reaching pitch link actuator **830a**.

Full-Authority IBC

The example radial fluid device **600**, described above, generates displacement changes to drive higher-harmonic motions (e.g., 2/rev through 6/rev) but does not necessarily generate fundamental cyclic motions (e.g., 1/rev). In some embodiments, it may be possible for radial fluid device **600** to provide fundamental cyclic motions by providing a single-lobed pump section similar to pump section **620**. In some circumstances, however, fundamental cyclic motions must be implemented more quickly than higher-harmonic motions because the pilot may steer the direction of the rotorcraft through fundamental cyclic motions. In these circumstances, the radial piston approach used by radial fluid device **600** to implement higher-harmonic motions may be too slow for fundamental cyclic motions. Thus, in some embodiments, the higher-harmonic approach described with regard to radial fluid device **600** may not be suitable for fundamental cyclic motions.

In some embodiments, it may also be possible to implement fundamental cyclic motions using the valves **812** of IBC system **800**. For example, valves **812** may be capable of changing fluid line pressures so as to implement fundamental cyclic motions on pitch link actuators **830a-830d**. As explained above, however, valves **812** may be more suitable for implementing small pressure changes, whereas fundamental cyclic motions may require large pressure changes in the fluid lines. Increasing the valve flow gain in valves **812** to implement these large pressure changes may increase the risk of hard-over failures. In addition, the power consumed and heat generated by valves **812** in this scenario may raise additional issues.

Teachings of certain embodiments recognize the capability to generate fundamental cyclic actuator motions quickly while still protecting against hard-over failures, conserving hydraulic power, and minimizing heat generation. Teachings of certain embodiments also recognize the capability to eliminate the mechanical rotor swashplate from a rotor system by hydraulically generating the fundamental cyclic motions.

FIGS. **13A-M** show a radial fluid device **900** according to one example embodiment. FIG. **13A** shows a side view of radial fluid device **900**, and FIG. **13B** shows a top view of radial fluid device **900**. Radial fluid device **900** features multiple stacked radial piston sections rotating together in conjunction with a common cylinder block **904** (not shown in FIGS. **13A** and **13B**).

In the example of FIGS. **13A-13M**, radial fluid device **900** features a fundamental cyclic pump **910** as well as stacked radial piston sections **920-960** and **920'-960'** rotating together with shaft **902**, cylinder block **904**, and manifold **970**. Embodiments of stacked radial piston sections **920-960** and **920'-960'** may resemble and operate similarly to stacked radial piston sections **620-660** and **620'-660'**.

As will be shown in greater detail below, shaft **902** is coupled to cylinder block **904**. In some embodiments, shaft **902** is removably coupled to cylinder block **904**. For example, different shafts **902** may have different gear splines, and an installer may choose from among different shafts **902** for use with radial fluid device **600**.

Cylinder block **904** rotates within radial fluid device **900**. In the example of FIGS. **10A-10M**, the axis of rotation of cylinder block **904** is coaxial with shaft **902**. Bearings may separate cylinder block **904** from the non-rotating body of radial fluid device **900**.

Fundamental cyclic pump **910** and each pump section pair (e.g., sections **920** and **920'**, **930** and **930'**, etc.) are dedicated to generating the desired waveform for a specific frequency. In the example of FIGS. **13A-13M**, fundamental cyclic pump **910** is dedicated to generating desired waveforms for fundamental cyclic motions (1/rev), and the pump section pairs are dedicated to generating desired waveforms for 2/rev through 6/rev.

Although the pump section pairs in radial fluid device **900** are dedicated to generating desired waveforms for 2/rev through 6/rev, teachings of certain embodiments recognize that other fluid devices may include pump sections dedicated to generating more, fewer, or different desired waveforms. For example, the performance benefits provided by some frequencies may be minimal, and the pump sections generating these frequencies would be eliminated. As one example, a variation of radial fluid device **900** may only feature pump sections dedicated to 2/rev (reactionless) and 4/rev (collective harmonic), with the fundamental cyclic motions (1/rev) generated by fundamental cyclic pump **910**.

Separate section frequencies from fundamental cyclic pump **910** and each pump section pair in radial fluid device **900** may be hydraulically summed together to generate a final desired waveform to each actuator, such as described above with regard to FIG. **9B**. In particular, as will be explained in greater detail below, manifold **970** transmits the hydraulically summed fluids from radial fluid device **900** to actuators corresponding to each blade in a rotor system.

FIG. **13C** shows a cross-section view of fundamental cyclic pump **910** along the cross-section line indicated in FIG. **13B**. Fundamental cyclic pump **910** features four pistons **911a-911d**. Each piston **911a-911d** is slidably received within a corresponding cylinder associated with chambers **904a-904d**. Each chamber **904a-904d** represents a plurality of cylinders within cylinder block **904** that are in fluid communication. Each chamber **904a-904d** may have an independent outlet port that exits radial fluid device **900** to control a different IBC actuator.

Fundamental cyclic pump **910** also features cam **912**. During operation, pistons **911a-911d** stroke inwards and outwards depending on the distance between cam **912** and the axis of rotation of cylinder block **904**. Each piston **911a-911d** reciprocates towards and away from the axis of rotation of cylinder block **604**. Each reciprocation towards and away from the axis of rotation thus includes two strokes: a down stroke and an up stroke.

In the example of FIG. **13C**, cam **912** is a circular cam and has one lobe. The number of lobes indicates how many sinusoidal stroke motions a piston completes during one full

## 23

rotation of cylinder block **904**. For example, each piston **911a-911d** completes one sinusoidal stroke motion during one rotation of cylinder block **904**. The ability of fundamental cyclic pump **910** to complete one sinusoidal stroke motion during one rotation corresponds to the one blade oscillation per revolution required for fundamental cyclic motions.

Repositioning cam **912** may change the displacement distance for each piston **911a-911d**. In the example of FIG. **13C**, positioning pistons **913**, **914**, and **915** may reposition cam **912**. In this example, positioning piston **913** is coupled to cam **912**, and positioning pistons **914** and **915** are coupled to a crank associated with cam **912**.

Cam **912** may be repositioned by varying the pressure in at least one of the cylinders associated with positioning pistons **913**, **914**, and **915**. Positioning pistons **913**, **914**, and **915** may allow cam **912** to be translated in two perpendicular axis, similar to swashplate lateral and longitudinal motions. The housing surrounding cam **912** may be dimensioned to provide stops limiting lateral and longitudinal cyclic travel.

In the example of FIG. **13C**, fluid in the cylinder associated with positioning piston **913** is maintained at a relatively constant system pressure, and fluid in the cylinders associated with positioning pistons **914** and **915** may be varied to reposition cam **912**. Positioning piston **913** may operate as a hydraulic spring to oppose the forces exerted by positioning pistons **914** and **915**.

In the example of FIG. **13C**, fundamental cyclic pump **910** includes position sensors **916** and **917**. Position sensors **916** and **917** may measure the displacement distance of positioning pistons **914** and **915**, respectively. One example of position sensor may include a linear variable differential transformer.

Valves **918** and **919** may provide fluid to the cylinders associated with positioning pistons **913**, **914**, and/or **915**. In some embodiments, valves **918** and **919** may change the size of their orifices to vary the pressure of fluid in the cylinders associated with positioning pistons **914** and **915**. In one example embodiment, valves **918** and **919** are three-way direct drive valves. In some embodiments, valves **918** and **919** may be single coil or dual coil three-way valves.

In some circumstances, if cylinder block **904** is rotating (such as at rotor speed) and cam **912** is positioned concentric with the input shaft axis, pistons **911a-911d** do not stroke. This scenario results in no fluid displacement control changes being sent to the IBC actuators for fundamental cyclic motions.

Translating cam **912** away from this concentric position, however, may result in fluid displacement control changes being sent to the IBC actuators for fundamental cyclic motions. FIG. **13D**, for example, shows how retracting positioning pistons **914** and **915** may reposition cam **912**. The example of FIG. **13D** may correspond to a full-forward longitudinal cyclic position in some scenarios. Moving cam **912** as shown in FIG. **13D** results in fundamental cyclic motions by each blade **120a-120d**, as shown in FIG. **13E**.

As another example, FIG. **13F** shows how extending positioning pistons **914** and **915** may reposition cam **912**. The example of FIG. **13F** may correspond to a full-aft cyclic position in some scenarios. Moving cam **912** as shown in FIG. **13F** results in fundamental cyclic motions by each blade **120a-120d**, as shown in FIG. **13G**. Comparing the examples of FIGS. **13E** and **13G**, blade **120a** in FIG. **13E** is 180 degrees out of phase with blade **120a** in FIG. **13G**.

Fundamental cyclic pump **910** may also implement lateral cyclic motions as well as longitudinal cyclic motions. FIG. **13H**, for example, shows how retracting positioning piston **914** and extending **915** may reposition cam **912**. The example

## 24

of FIG. **13H** may correspond to a full-left lateral cyclic position in some scenarios. Moving cam **912** as shown in FIG. **13H** results in fundamental cyclic motions by each blade **120a-120d**, as shown in FIG. **13I**.

As another example, FIG. **13J** shows how extending positioning piston **914** and retracting positioning piston **915** may reposition cam **912**. The example of FIG. **13J** may correspond to a full-right longitudinal position in some scenarios. Moving cam **912** as shown in FIG. **13J** results in fundamental cyclic motions by each blade **120a-120d**, as shown in FIG. **13K**. Comparing the examples of FIGS. **13I** and **13K**, blade **120a** in FIG. **13I** is 180 degrees out of phase with blade **120a** in FIG. **13K**. Comparing the examples of FIGS. **13E** and **13I**, blade **120a** in FIG. **13E** is 90 degrees out of phase with blade **120a** in FIG. **13I**.

In the example of FIGS. **13A-13K**, fundamental cyclic pump **910** is configured to provide fundamental cyclic motions in a four blade rotor system. Teachings of certain embodiments recognize, however, recognize that the concepts described with regard to fundamental cyclic pump **910** may be adapted to support IBC for rotor systems with more or fewer blades (e.g., two blades, three blades, five blades, six blades, seven blades, etc.).

For example, FIG. **13L** shows a fundamental cyclic pump **910'** configured to provide IBC in a five-blade rotor system. In this example, fundamental cyclic pump **910'** features five pistons **911a'-911e'** corresponding to each blade in the five-blade rotor system. Fundamental cyclic pump **910'** also features a cam **912'**, positioning pistons **913'-915'**, position sensors **916'** and **917'**, and valves **918'** and **919'** that may operate in a similar manner to corresponding components in fundamental cyclic pump **910**.

FIG. **13M** shows a cross-section view of radial fluid device **900** along the cross-section line indicated in FIG. **13B**. As shown in FIG. **13M**, fundamental cyclic pump **910** and all pump sections generating frequencies 2/rev through 6/rev are situated about the same cylinder block **904**. In addition, fundamental cyclic pump **910** and all pump sections share the same chambers **904a-904d**. Each chamber **904a-904d** is ported out of radial fluid device **900** through manifold **970**. Manifold **970** may enable fluid communication between each chamber **904a-904d** and a corresponding actuator with rotor blades **120a-120d** (e.g., fluid communication between chamber **904a** and the actuator associated with rotor blade **120a**).

In some embodiments, cylinder block **904** may rotate at the same speed as drive shaft **112b**. Teachings of certain embodiments recognize that rotating cylinder block **904** at the same speed as drive shaft **112b** may allow harmonic outputs from radial fluid device **900** to be synchronized with the rotor blades **120a-120d** rotating about drive shaft **112b**. In the example of FIG. **13M**, an exterior power source rotates shaft **902** at the same speed as drive shaft **112b**, which causes cylinder block **904** to also rotate at the same speed.

Implementing Full-Authority IBC

As stated above, radial fluid device **900** may provide sinusoidal waveform amplitude and synchronization displacement control to multiple actuators for use in a full-authority IBC system. For example, radial fluid device **900** may include a fundamental cyclic pump and pump section pairs dedicated to generating desired waveforms for 1/rev through 6/rev. In this example, the mechanical swashplate, such as swashplate **116** of FIG. **2**, may be eliminated of the rotor system. As will be explained in greater detail below, teachings of certain embodiments recognize the capability to convert harmonic pressure changes in hydraulic fluid within radial fluid device **900** into movements of blades **120a-120d**.

25

FIG. 14A shows an IBC system 1000 according to one example embodiment. IBC system 1000 is a full-authority IBC system that features radial fluid device 900, a hydraulic control manifold 1100, a hydraulic swivel 1200, four blade actuators 1300a-1300d (corresponding to rotor blades 120a-120d), a hydraulic pump 1400, a hydraulic reservoir 1500, and a heat exchanger 1600.

As shown in FIGS. 14A-14C and 15A-15E, IBC system 1000 may include a variety of fluid lines that provide fluid communication between multiple components. For convenience, some of these fluid lines have been labeled "a," "b," "c," "d," "e," or "f." In these example embodiments, labels "a"-"d" correspond with chambers 904a-904d and blades 120a-120d. For example, fluid line "a" may represent a fluid line in the path between chamber 904a and blade 120a. Fluid line "e" may refer to system fluid, and fluid line "f" may refer to return fluid, both of which are described in greater detail below.

In operation, according to one example embodiment, radial fluid device 900 provides hydraulic fluid to hydraulic control manifold 1100. Hydraulic control manifold directs the fluid through hydraulic swivel 1200, which is configured to transfer the fluid flow from the fixed-frame portion of the rotorcraft to the rotating-frame portion of the rotorcraft. In one example embodiment, hydraulic swivel 1200 provides the fluid up along the drive shaft to blade actuators 1300a-1300d, which converts pressure changes in the supplied hydraulic fluid into movements of rotor blades 120a-120d.

In addition to providing fluid from radial fluid device 900 to blade actuators 1300a-1300d, IBC system 1000 also provides system fluid from hydraulic pump 1400 to blade actuators 1300a-1300d. This system fluid represents a constant-pressure fluid supply. Teachings of certain embodiments recognize that the supply fluid may not necessarily stay constant, such as due to leakage or other effects that may change the pressure of the supply fluid. The supply fluid may be provided to blade actuators 1300a-1300d to provide a balance against the pressures of the hydraulic fluid from radial fluid device 900. Excess fluid may also be accumulated through hydraulic control manifold 1100 and hydraulic swivel 1200, passed through heat exchanger 1600, and stored in hydraulic reservoir 1500 before being resupplied to hydraulic pump 1400.

FIG. 14B shows hydraulic control manifold 1100 according to one example embodiment. Hydraulic control manifold 1100 features valves 1112 and control ports 1114.

In operation, according to one example embodiment, hydraulic control manifold 1100 receives fluid from chambers 904a-904d of radial fluid device 900 and communicates the fluid to valves 1112 and control ports 1114. In this example embodiment, hydraulic control manifold 1100 receives the fluid from chambers 904a-904d through manifold 970, which rotates with cylinder block 904. Manifold 970 includes ports for each chamber 904a-904d. In addition, manifold 970 includes seals around each port for chambers 904a-904d. Furthermore, manifold 970 includes return ports to accumulate leaking hydraulic fluid and return the accumulated hydraulic fluid to reservoir 1500.

Radial fluid device 900 may not include provisions for independently trimming blade actuator stroke position to equalize their lengths and maintain IBC operation about a center stroke. Accordingly, hydraulic control manifold 1100 may include valves 1112 operable to trim the position of each blade actuator 1300a-1300d and to compensate for leaking hydraulic fluid. In one example embodiment, valves 1112 are three-way direct drive valves.

26

Valves 1112 may add supply fluid to fluid lines a-d if the fluid pressure falls below a threshold. Alternatively, valves 1112 may remove fluid from fluid lines a-d if the fluid pressure rises about a threshold. In one example embodiment, valves 1112 receives measurements from position sensors associated with blade actuators 1300a-1300d and then adds fluid to or removes fluid from fluid lines a-d based on the received measurements. The measurements from the position sensors may indicate, for example, the amount of fluid that has leaked from various fluid lines within IBC system 1000. As another example, the measurements from the position sensors may indicate whether fluid line pressure should be adjusted to trim the position of each blade actuators 1300a-1300d.

In one example embodiment, valves 1112 may adjust for drift and leakage in IBC system 1000, but valves 1112 may not drive high-frequency changes in system pressure. Rather, high-frequency changes may be implemented by radial fluid device 900. Teachings of certain embodiments recognize that only using valves for low-frequency changes in system pressure may reduce the necessary size of the valves and increase longevity of the valves.

Unlike partial-authority IBC system 800, full-authority IBC system 1000 includes two valves 1112 for each rotor blade (e.g., two valves 1112a for rotor blade 120a). Teachings of certain embodiments recognize that multiple valves 1112 may be capable of providing fundamental collective input. In some embodiments, additional valves 1112 may add or remove fluid from the volume trapped between radial fluid device 900 and blade actuators 1300. Because the high-frequency flow providing fundamental cyclic and IBC is controlled by radial fluid device 900, valves 900 may be relatively low gain, thus minimizing the impact of a valve hard-over failure.

Even with a relatively low gain, a valve hard-over failure on a full-authority IBC actuator could create rotor instability if not bypassed quickly. Teachings of certain embodiments recognize that redundant systems may be appropriate for full-authority IBC systems because of the risks associated with removing the mechanical swashplate from the rotor system. Accordingly, the example full-authority IBC system 1000 includes redundant valves 1112 for each rotor blade. By incorporating two valves per IBC actuator, hard-over failures may be quickly bypassed by commanding the second valve in the opposite direction.

Control ports 1114 communicate fluid between hydraulic control manifold 1100 and hydraulic swivel 1200. Teachings of certain embodiments recognize that control ports 1114 may also terminate fluid flow in the event of some system failures. In the example of FIG. 14B, each control port 1114 is equipped with a solenoid bypass valve. In the event of a full-authority system failure requiring isolation from the conventional flight control system, for example, IBC system 1000 may remove power to the solenoid bypass valves associated with each control port 1114. In response, control ports 1114 cut off pressure to their pressure relief/bypass valves, causing them to redirect system fluid to the hydraulic fluid return lines f that lead back to reservoir 1500.

As will be explained in greater detail below with regard to FIGS. 17A and 17B, two or more radial fluid devices 900 may operate in parallel. In this scenario, damaging control force fighting between IBC actuators may occur if the displacement control outputs are not correctly synchronized. Should pressure synchronization fail or a blade actuator be inadvertently bottomed on a stationary vane, for example, damaging control pressures and actuator loads can be induced.



Teachings of certain embodiments recognize the ability to provide position sensors for synchronizing operations between multiple radial fluid devices **900**. In some embodiments, position sensors may be provided on positioning pistons **913-915** (which are discussed above with regards to FIGS. **13A-13K**) and/or the higher-harmonic cams of each radial fluid device **900**. In these embodiments, however, the position sensors may not have the appropriate resolution to control force fights in a rigid system. Accordingly, teachings of certain embodiments recognize the capability to monitor control port pressure for each IBC actuator to control force fights between IBC actuators. In one example embodiment, each control port **1114** includes a position sensor **1116**. Position sensors **1116** may measure the displacement distance of the control valve associated with each control port **1114**. One example of position sensor may include a linear variable differential transformer.

In some embodiments, each control port **1114** may respond to changes in control port pressure by displacing its control valve proportionally to the pressure change. Each position sensor **1116** may measure the amount of displacement of each control valve. If control port pressure exceeds an allowable threshold, valves **1114** may port excess pressure to the return fluid system. Valves **1114** may isolate the system following a failure by applying electric power to the solenoids associated with valves **1114** and causing all control ports **1114** to port fluid to the return fluid system, effectively bypassing the entire system.

FIG. **14C** shows hydraulic swivel **1200** according to one example embodiment. Hydraulic swivel **1200** includes a rotating portion **1222** and a stationary portion **1224**. Rotating portion **1222** includes ports **1222a-1222d** that communicates fluid between blade actuators **1300a-1300d** and non-rotating portion **1224**. Rotating portion **1222** also includes port **1222e**, which communicates system fluid between blade actuators **1300a-1300d** and non-rotating portion **1224**. Rotating portion **1222** includes port **1222f**, which communicates return fluid between blade actuators **1300a-1300d** and non-rotating portion **1224**.

Rotating portion also includes rotary seals **1223** between each port **1222a-1222f**. Teachings of certain embodiments recognize that providing both port **1222f** for return fluid and seals **1223** may extend seal life and reduce or eliminate issues associated with nuisance leakage.

Rotating portion also includes wiring for communicating signals from blade actuators **1300a-1300d** to the non-rotating portions of IBC system **1000**. In one example embodiment, the wiring includes two wires for each position sensor associated with the blade actuators **1300a-1300d** plus three common wires for each blade actuator providing excitation power.

Stationary portion **1224** includes fluid lines **1224a-1224d** that communicates fluid between ports **1222a-1222d** and fluid lines a-d. Stationary portion **1224** also includes fluid line **1224e**, which communicates fluid between port **1222e** and fluid line e. Stationary portion **1224** includes fluid line **1224f**, which communicates fluid between port **1222f** and fluid line f.

FIGS. **15A-15F** show blade actuator **1300a** according to one example embodiment. FIG. **15A** shows a top view of blade actuator **1300a**, and FIG. **15B** shows a side view of blade actuator **1300a**. Blade actuator **1300a** is operable to change the position of blade **120a** during operation of rotorcraft **100**. Similarly, blade actuators **1300b-1300d** are operable to change the positions of blades **120b-120d**, respectively.

In the example of FIGS. **15A-15F**, blade actuator **1300a** is a hydraulic rotary vane actuator. In some embodiments, a hydraulic rotary vane actuator may be powered at the root of

each rotor blade. Teachings of certain embodiments recognize that vane actuators may have reduced leakage due to their dependency on a rotary seal, as compared to an equivalent-power linear hydraulic actuator with a sliding seal. In addition, a hydraulic vane actuator may also have a higher relative stiffness.

As shown in FIGS. **15A** and **15B**, blade actuator **1300a** may feature a shaft **1302** and a rotary seal **1304** disposed within one or more openings of a housing **1310**. As will be shown in greater detail below, shaft **1302** is coupled to a vane within housing **1310**. In some embodiments, different shafts **1302** may have different gear splines, and an installer may choose from among different shafts **1302** for use with different rotor blades. Rotary seal **1304** is positioned about shaft **1302** and separates the interior of housing **1310** from the exterior of housing **1310**.

In some embodiments, rotary seal **1304** is an elastomeric membrane seal. Teachings of certain embodiments recognize that an elastomeric membrane seal may be suitable in situations where shaft **1302** is limited to a certain range of motion. For example, an elastomeric seal may be coupled to shaft **1302** and may stretch as shaft **1302** rotates so long as shaft **1302** does not stretch the elastomeric seal past its elasticity limit. In some embodiments, angular travel of shaft **1302** may be limited to plus/minus 18 degrees of rotation. In these embodiments, the elastomeric membrane seal may stretch to absorb the plus/minus 18 degrees of rotation. In addition, as will be explained below with regard to FIG. **15D**, the elastomeric membrane seal may not be exposed to high pressures (e.g., return fluid pressure of approximately 100 pounds per square inch), thus limiting the axial hydraulic forces pushing against the seal.

In the example of FIGS. **15A** and **15B**, housing **1310** includes multiple pieces connected together using bolts **1312**. Housing **1310** may also include connection points **1314** for securing blade actuator **1300a** to the rotorcraft.

FIG. **15C** shows a cross-section view of blade actuator **1300a** along the cross-section line indicated in FIG. **15B**. As seen in FIG. **15C**, blade actuator **1300a** features stationary vanes **1320** and vane impeller **1330**. In this example, stationary vanes **1320** define three chambers, although other embodiments may define more or fewer chambers. Vane impeller **1330** includes three vane surfaces, each vane surface extending into a corresponding chamber between stationary vanes **1320**. Vane impeller **1330** is coupled to shaft **1302** such that rotation of vane impeller **1330** results in rotation of shaft **1302**.

Each chamber defined by stationary vanes **1320** includes two openings for communicating fluid into and out of the chamber. Within each chamber, the vane surface of vane impeller **1330** separates the two openings such that fluid from both openings may accumulate and pressurize on both sides of the vane surface. In operation, a difference in fluid pressure on opposite sides of a vane surface may cause the vane surface (and thus vane impeller **1330** as a whole) to rotate.

In the example of FIG. **15C**, each chamber includes variable-pressure control fluid **1322** on one side of a vane surface. In two chambers, return fluid **1324** is accumulated and ported out of blade actuator **1300**. In these two chambers, the pressure of the control fluid **1322** is expected to be greater than the pressure of the return fluid **1324**. In the third chamber, approximately-constant system fluid **1326** is provided opposite the variable-pressure control fluid **1324**. In this third chamber, the system fluid **1326** applies a constant source of hydraulic pressure to oppose pressure from the control fluid **1322** and create a hydraulic spring effect. In this example, the first two chambers, in combination, have twice the effective



29

vane area as the third chamber, doubling the ability of the variable-pressure control fluid **1322** to move vane impeller **1330**.

In some circumstances, blade actuator **1300a** may be subject to leakage. For example, leakage across rectangular vane surfaces in a rotary vane may be higher than in piston actuators in a cylinder. Accordingly, teachings of certain embodiments recognize that leaked fluid should be ported returned to the system rather than vented to the atmosphere. Teachings of certain embodiments also recognize the ability to use this leaked fluid to provide a continuous lubrication to support bearings in blade actuator **1300a** and create low pressure areas behind rotary seals **1304**.

FIG. **15D** shows a cross-section view of blade actuator **1300a** along the cross-section line indicated in FIG. **15A**. As shown in FIG. **15D**, support bearings **1340** may support rotation of shaft **1302** within blade actuator **1300a**. In this example, leaking fluid may lubricate support bearings **1340** and then be ported to the return fluid **1324**. In addition, teachings of certain embodiments recognize that providing return fluid **1324** behind rotary seal **1304** may prevent rotary seal **1304** from being subject to high hydraulic forces.

FIGS. **15E** and **15F** show cross-section views of blade actuator **1300a** along the cross-section line indicated in FIG. **15B** during operation of blade actuator **1300a**. In the example of FIG. **15E**, hydraulic pressure of control fluid **1322** is greater than hydraulic pressure of system fluid **1326**, which forces vane impeller **1330** to rotate counter-clockwise by 18 degrees. In the example of FIG. **15F**, hydraulic pressure of control fluid **1322** is less than hydraulic pressure of system fluid **1326**, which forces vane impeller **1330** to rotate clockwise by 18 degrees.

In some embodiments, multiple blade actuators **1300** may be coupled together to operate in series. Teachings of certain embodiments recognize that providing multiple blade actuators **1300** per blade may provide redundancy and reduce catastrophic failure in the event a blade actuator fails. For example, FIG. **16A** shows two blade actuators **1300a** coupled together in series, and FIG. **16B** shows three blade actuators **1300a** coupled together in series. In each of these examples, coupling assemblies **1350** couple together shafts **1302a** from different blade actuators **1300a**.

FIGS. **17A** and **17B** show redundant IBC systems having multiple blade actuators **1300** coupled together in series. In FIG. **17A**, IBC system **2000** features three blade actuators **1300** coupled together in series for each rotary blade (e.g., rotor blade **120a** is coupled to three blade actuators **1300a**). IBC system **2000** also features three flight control computers (flight control computers **2100**, **2200**, and **2300**). Each flight control computer is in communication with a corresponding radial fluid device **900**. Each flight control computer/radial fluid device combination is operable to control one of the three blade actuators **1300** for each rotor blade, as shown in FIG. **17A**.

In operation, according to one example embodiment, flight control computers **2100**, **2200**, and **2300** receive cyclic and collective instructions from input device **2050**. One example of input device **2050** may include a control stick accessible by a pilot. Each flight control computer **2100**, **2200**, and **2300** programs a radial fluid device **900** to implement the cyclic and collective instructions. For example, each flight control computer may send signals indicating how the fundamental cyclic motion pistons and the higher-harmonic cams of each radial fluid device should be positioned.

Each flight control computer **2100**, **2200**, and **2300** may also receive measurements indicating whether blade actuators **1300** are fighting against one another. For example, each

30

flight control computer may measure shaft rotation speeds, fluid pressures, and/or piston/valve displacements. In this example, a difference in these measurements between flight control computers **2100**, **2200**, and **2300** may indicate that two or more blade actuators **1300** may be fighting each other. Thus, flight control computers **2100**, **2200**, and **2300** may communicate with each other using cross-channel data links to share synchronization information. As one example, if two blade actuators **1300** are mechanically fighting, the two corresponding flight control computers may share information indicating that at least one of the flight control computers should adjust fluid line pressure within its portion of the IBC system.

In FIG. **17B**, IBC system **3000** features two blade actuators **1300** coupled together in series for each rotary blade (e.g., rotor blade **120a** is coupled to two blade actuators **1300a**). IBC system **3000** also features four flight control computers (flight control computers **3100**, **3200**, **3300**, and **3400**). Unlike IBC system **2000**, two flight control computers are in communication with one corresponding radial fluid device **900**. In this example, each radial fluid device **900** is in communication with redundant flight control computers, allowing each radial fluid device **900** to continue powering blade actuators **1300** even if one flight control computer is disabled.

Teachings of certain embodiments recognize that IBC systems may include any number of blade actuators, flight control computers, and radial fluid devices. The numbering and configuration may depend, for example, on the safety requirements for a particular rotorcraft.

Modifications, additions, or omissions may be made to the systems and apparatuses described herein without departing from the scope of the invention. The components of the systems and apparatuses may be integrated or separated. Moreover, the operations of the systems and apparatuses may be performed by more, fewer, or other components. The methods may include more, fewer, or other steps. Additionally, steps may be performed in any suitable order.

Although several embodiments have been illustrated and described in detail, it will be recognized that substitutions and alterations are possible without departing from the spirit and scope of the present invention, as defined by the appended claims.

To aid the Patent Office, and any readers of any patent issued on this application in interpreting the claims appended hereto, applicants wish to note that they do not intend any of the appended claims to invoke paragraph 6 of 35 U.S.C. §112 as it exists on the date of filing hereof unless the words “means for” or “step for” are explicitly used in the particular claim.

What is claimed is:

1. A rotorcraft, comprising:

a body;

a power train coupled to the body and comprising a power source and a drive shaft coupled to the power source;

a rotor system coupled to the power train and comprising a rotor blade; and

a rotary actuator coupled to the at least one rotor blade, the rotary actuator comprising:

a housing comprising a first chamber and a second chamber, wherein the first chamber features a first fluid opening and a second fluid opening and the second chamber features a third fluid opening and a fourth fluid opening;

a first fluid source in fluid communication with the first and third fluid openings and configured to provide a first fluid to the first chamber and the second chamber at a first pressure;

31

a second fluid source in fluid communication with the second fluid opening and configured to provide a second fluid to the first chamber at a second pressure;  
 a third fluid source in fluid communication with the fourth fluid opening and configured to provide a third fluid to the second chamber at a third pressure different than the second pressure;  
 a vane disposed within the housing, the vane comprising a first vane surface disposed within the first chamber between the first fluid opening and the second fluid opening and a second vane surface disposed within the second chamber between the third fluid opening and the fourth fluid opening; and  
 a shaft disposed at least partially within the housing and coupled to the vane, wherein the shaft is coupled to the rotor blade such that the shaft transfers movement of the vane to the rotor blade.

2. The rotorcraft of claim 1, further comprising at least one fluid pump operable to provide the first fluid through the first fluid opening and the third fluid opening and provide the second fluid through the second fluid opening.

3. The rotorcraft of claim 1, wherein the first fluid has a varying pressure and the second fluid has an approximately constant pressure.

4. The rotorcraft of claim 1, wherein:

the housing further comprises a third chamber featuring a fifth fluid opening and a sixth fluid opening;

the first fluid source is in fluid communication with the fifth opening and configured to provide the first fluid to the third chamber at the first pressure;

the third fluid source is in fluid communication with the sixth opening and configured to provide the third fluid to the third chamber at the third pressure; and

the vane further comprises a third surface disposed within the third chamber between the fifth fluid opening and the sixth fluid opening.

5. The rotorcraft of claim 1, the rotary actuator further comprising a plurality of bearings separating the shaft from the housing.

6. The rotorcraft of claim 5, the housing further comprising at least one surface configured to direct at least some leaking fluid from the first chamber or the second chamber through a portion of at least one of the plurality of bearings.

7. The rotorcraft of claim 1, the rotary actuator further comprising an elastomeric seal coupled to the shaft and to the housing, the elastomeric seal configured to prevent at least some fluid from leaking out of the rotary actuator between the shaft and the housing.

8. The rotorcraft of claim 1, wherein the first vane surface separates the first fluid from the second fluid within the first chamber and the second vane surface separates the first fluid from the third fluid within the second chamber.

9. The rotorcraft of claim 1, wherein the vane is operable to rotate in response to a difference in forces applied against the vane by the first fluid in a first direction and by the second and third fluids in an opposing second direction.

10. The rotorcraft of claim 4, wherein the third vane surface separates the first fluid from the third fluid within the third chamber.

32

11. A rotary blade actuator, comprising:

a housing comprising a first chamber and a second chamber, wherein:

the first chamber features a first fluid opening and a second fluid opening and the second chamber features a third fluid opening and a fourth fluid opening,

the first and third fluid openings are configured to provide a first fluid to the first chamber and the second chamber at a first pressure,

the second fluid opening is configured to provide a second fluid to the first chamber at a second pressure, and the fourth fluid opening is configured to provide a third fluid to the second chamber at a third pressure different from the second pressure;

a vane disposed within the housing, the vane comprising a first vane surface disposed within the first chamber between the first fluid opening and the second fluid opening and a second vane surface disposed within the second chamber between the third fluid opening and the fourth fluid opening;

a shaft disposed at least partially within the housing and coupled to the vane, the shaft operable to rotate in response to movements of the vane.

12. The rotary blade actuator of claim 11, wherein the first fluid has a varying pressure and the second fluid has an approximately constant pressure.

13. The rotary blade actuator of claim 11, wherein:

the housing further comprises a third chamber featuring a fifth fluid opening and a sixth fluid opening;

the fifth fluid opening is configured to provide the first fluid to the third chamber at the first pressure;

the sixth fluid opening is configured to provide the third fluid to the third chamber at the third pressure; and

the vane further comprises a third surface disposed within the third chamber between the fifth fluid opening and the sixth fluid opening.

14. The rotary blade actuator of claim 11, further comprising a plurality of bearings separating the shaft from the housing.

15. The rotary blade actuator of claim 14, the housing further comprising at least one surface configured to direct at least some leaking fluid from the first chamber or the second chamber through a portion of at least one of the plurality of bearings.

16. The rotary blade actuator of claim 14, further comprising an elastomeric seal coupled to the shaft and to the housing, the elastomeric seal configured to prevent at least some fluid from leaking out of the rotary actuator between the shaft and the housing.

17. The rotary blade actuator of claim 11, wherein the first vane surface separates the first fluid from the second fluid within the first chamber and the second vane surface separates the first fluid from the third fluid within the second chamber.

18. The rotary blade actuator of claim 11, wherein the vane is operable to rotate in response to a difference in forces applied against the vane by the first fluid in a first direction and by the second and third fluids in an opposing second direction.

19. The rotary blade actuator of claim 13, wherein the third vane surface separates the first fluid from the third fluid within the third chamber.

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